



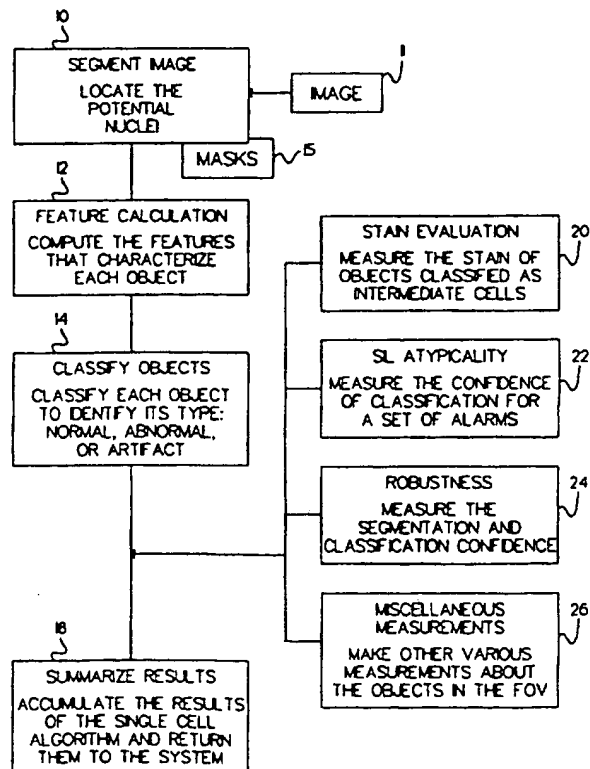
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## Title: APPARATUS FOR THE IDENTIFICATION OF FREE-LYING CELLS

## (57) Abstract

A free-lying cell classifier. An automated microscope system (511) comprising a computer (540) and high speed processing field of view processors (568) identifies free-lying cells (80, 82). An image (11) of a biological specimen is obtained and the image (11) is segmented (10) to create a set of binary masks (15). The binary masks (15) are used by a feature calculator (12) to compute the features that characterize objects of interest (80, 82) including free-lying cells, artifacts and other biological objects. The objects (80, 82) are classified to identify their type, their normality or abnormality or their identification as an artifact. The results are summarized and reported (18). A stain evaluation (20) of the slide is performed as well as a typicality evaluation (22). The robustness (24) of the measurement is also quantified as a classification confidence value (216). The free-lying cell evaluation is used by an automated cytology system (500) to classify a biological specimen slide.



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**APPARATUS FOR THE IDENTIFICATION OF FREE-LYING CELLS**

The invention relates to an automated cytology system and more particularly to an automated cytology that identifies and classifies free-lying cells and cells having isolated nuclei on a biological specimen slide.

**BACKGROUND OF THE INVENTION**

One goal of a Papanicolaou smear analysis system is to emulate the well established human review process which follows standards suggested by The Bethesda System. A trained cytologist views a slide at low magnification to identify areas of interest, then switches to higher magnification where it is possible to distinguish normal cells from potentially abnormal ones according to changes in their structure and context. In much the same way as a human reviews Papanicolaou smears, it would be desirable for an automated cytology analysis system to view slides at low magnification to detect possible areas of interest, and at high magnification to locate possible abnormal cells. As a cytologist compares size, shape, texture, context and density of cells against established criteria, so it would be desirable to analyze cells according to pattern recognition criteria established during a training period.

**SUMMARY OF THE INVENTION**

The invention identifies and classifies free-lying cells and cells having isolated nuclei on a biological specimen: single cells. Objects that appear as single cells bear the most significant diagnostic information in a pap smear. Objects that appear as single cells may be classified as being either normal cells, abnormal cells, or artifacts. The invention also provides a confidence level indicative of the likelihood that an object has been

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correctly identified and classified. The confidence level allows the rejection of slides having only a few very confident abnormal cells. The staining characteristics of the slide are also evaluated. The invention first acquires an image of the biological specimen at a predetermined magnification. Objects found in the image are identified and classified. This information is used for subsequent slide classification.

10 In one embodiment, the invention utilizes a set of statistical decision processes that identify potentially neoplastic cells in Papanicolaou-stained cervical/vaginal smears. The decisions in accordance with the invention as to whether an individual cell is  
15 normal or potentially neoplastic are used to determine if a slide is clearly normal or requires human review. The apparatus of the invention uses nuclear and cytoplasm detection with classification techniques to detect and identify free-lying cells and cells having  
20 isolated nuclei. The apparatus of the invention can detect squamous intraepithelial lesion (SIL) or other cancer cells.

In addition to the detection and classification of single cells, the invention measures the specimen  
25 cell population to characterize the slide. Several measures of stain related features are measured for objects which are classified as intermediate squamous cells. Also, many measures are made of the confidence with which objects are classified at various stages in  
30 the single cell algorithm. All of this information is used in conjunction with the number of potentially neoplastic cells to determine a final slide score. The invention performs three levels of processing: image segmentation, feature extraction, and object  
35 classification.

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Other objects, features and advantages of the present invention will become apparent to those skilled in the art through the description of the preferred embodiment, claims and drawings herein  
5 wherein like numerals refer to like elements.

#### BRIEF DESCRIPTION OF THE DRAWINGS

To illustrate this invention, a preferred embodiment will be described herein with reference to the accompanying drawings.

10 Figures 1A, 1B and 1C show the automated cytology screening apparatus of the invention.

Figure 2 shows the method of the invention to arrive at a classification result from an image.

15 Figure 3A shows the segmentation method of the invention.

Figure 3B shows the contrast enhancement method of the invention.

20 Figures 3C and 3D show a plot of pixels vs. brightness.

Figure 3E shows the dark edge incorporated image method of the invention.

Figure 3F shows the bright edge removal method of the invention.

25 Figures 3G, 3H and 3I show refinement of an image by small hole removal.

Figure 4A shows the feature extraction and object classification of the invention.

Figure 4B shows an initial box filter.

Figure 4C shows a stage 1 classifier.

30 Figure 4D shows a stage 2 classifier.

Figure 4E shows a stage 3 classifier.

Figures 4F and 4G show an error graph.

Figure 5 shows a stain histogram.

Figure 6A shows robust and non-robust objects.

35 Figure 6B shows a decision boundary.

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Figure 6C shows a segmented object.

Figure 7A shows a threshold graph.

Figure 7B shows a binary decision tree.

Figure 8 shows a stage 4 classifier.

5 Figure 9 shows a ploidy classifier.

#### DETAILED DESCRIPTION OF THE PREFERRED EMBODIMENT

10 In a presently preferred embodiment of the invention, the system disclosed herein is used in a system for analyzing cervical pap smears, such as that shown and disclosed in U.S. Patent Application Serial No. 07/838,064, entitled "Method For Identifying Normal Biomedical Specimens", by Alan C. Nelson, et al., filed February 18, 1992; U.S. Patent Application Serial No. 08/179,812 filed January 10, 1994 which is  
15 a continuation in part of U.S. Patent Application Serial No. 07/838,395, entitled "Method For Identifying Objects Using Data Processing Techniques", by S. James Lee, et al., filed February 18, 1992; U.S. Patent Application Serial No. 07/838,070, now U.S.  
20 Pat. No. 5,315,700, entitled "Method And Apparatus For Rapidly Processing Data Sequences", by Richard S. Johnston, et al., filed February 18, 1992; U.S. Patent Application Serial No. 07/838,065, filed 02/18/92, entitled "Method and Apparatus for Dynamic Correction  
25 of Microscopic Image Signals" by Jon W. Hayenga, et al.; and U.S. Patent Application Serial No. 08/302,355, filed September 7, 1994 entitled "Method and Apparatus for Rapid Capture of Focused Microscopic Images" to Hayenga, et al., which is a continuation-in-part of Application Serial No. 07/838,063 filed on  
30 February 18, 1992 the disclosures of which are incorporated herein, in their entirety, by the foregoing references thereto.

35 The present invention is also related to biological and cytological systems as described in the

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following patent applications which are assigned to the same assignee as the present invention, filed on September 20, 1994 unless otherwise noted, and which are all hereby incorporated by reference including

5 U.S. Patent Application Serial No. 08/309,118, to Kuan et al. entitled, "Field Prioritization Apparatus and Method," U.S. Patent Application Serial No. 08/309,061, to Wilhelm et al., entitled "Apparatus for Automated Identification of Cell Groupings on a

10 Biological Specimen," U.S. Patent Application Serial No. 08/309,116 to Meyer et al. entitled "Apparatus for Automated Identification of Thick Cell Groupings on a Biological Specimen," U.S. Patent Application Serial No. 08/309,115 to Lee et al. entitled "Biological

15 Analysis System Self Calibration Apparatus," U.S. Patent Application Serial No. 08/308,992, to Lee et al. entitled "Apparatus for Identification and Integration of Multiple Cell Patterns," U.S. Patent Application Serial No. 08/309,063 to Lee et al.

20 entitled "A Method for Cytological System Dynamic Normalization," U.S. Patent Application Serial No. 08/309,248 to Rosenlof et al. entitled "Method and Apparatus for Detecting a Microscope Slide Coverslip," U.S. Patent Application Serial No. 08/309,077 to

25 Rosenlof et al. entitled "Apparatus for Detecting Bubbles in Coverslip Adhesive," U.S. Patent Application Serial No. 08/309,931, to Lee et al. entitled "Cytological Slide Scoring Apparatus," U.S. Patent Application Serial No. 08/309,148 to Lee et al.

30 entitled "Method and Apparatus for Image Plane Modulation Pattern Recognition," U.S. Patent Application Serial No. 08/309,209 to Oh et al. entitled "A Method and Apparatus for Robust Biological Specimen Classification," U.S. Patent Application

35 Serial No. 08/309,117, to Wilhelm et al. entitled

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"Method and Apparatus for Detection of Unsuitable Conditions for Automated Cytology Scoring."

5 It is to be understood that the various processes described herein may be implemented in software suitable for running on a digital processor. The software may be embedded, for example, in the central processor 540.

10 Now refer to Figures 1A, 1B and 1C which show a schematic diagram of one embodiment of the apparatus of the invention for field of view prioritization. The apparatus of the invention comprises an imaging system 502, a motion control system 504, an image processing system 536, a central processing system 540, and a workstation 542. The imaging system 502  
15 is comprised of an illuminator 508, imaging optics 510, a CCD camera 512, an illumination sensor 514 and an image capture and focus system 516. The image capture and focus system 516 provides video timing data to the CCD cameras 512, the CCD cameras 512  
20 provide images comprising scan lines to the image capture and focus system 516. An illumination sensor intensity is provided to the image capture and focus system 516 where an illumination sensor 514 receives the sample of the image from the optics 510. In one  
25 embodiment of the invention, the optics may further comprise an automated microscope 511. The illuminator 508 provides illumination of a slide. The image capture and focus system 516 provides data to a VME bus 538. The VME bus distributes the data to an image  
30 processing system 536. The image processing system 536 is comprised of field-of-view processors 568. The images are sent along the image bus 564 from the image capture and focus system 516. A central processor 540 controls the operation of the invention through the  
35 VME bus 538. In one embodiment the central processor



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562 comprises a MOTOROLA 68030 CPU. The motion controller 504 is comprised of a tray handler 518, a microscope stage controller 520, a microscope tray controller 522, and a calibration slide 524. The motor drivers 526 position the slide under the optics. A bar code reader 528 reads a barcode located on the slide 524. A touch sensor 530 determines whether a slide is under the microscope objectives, and a door interlock 532 prevents operation in case the doors are open. Motion controller 534 controls the motor drivers 526 in response to the central processor 540. An Ethernet communication system 560 communicates to a workstation 542 to provide control of the system. A hard disk 544 is controlled by workstation 550. In one embodiment, workstation 550 may comprise a SUN SPARC CLASSIC (TM) workstation. A tape drive 546 is connected to the workstation 550 as well as a modem 548, a monitor 552, a keyboard 554, and a mouse pointing device 556. A printer 558 is connected to the ethernet 560.

During object identification and classification, the central computer 540, running a real time operating system, controls the microscope 511 and the processor to acquire and digitize images from the microscope 511. The flatness of the slide may be checked, for example, by contacting the four corners of the slide using a computer controlled touch sensor. The computer 540 also controls the microscope 511 stage to position the specimen under the microscope objective, and from one to fifteen field of view (FOV) processors 568 which receive images under control of the computer 540.

The computer system 540 accumulates results from the 4x process and performs bubble edge detection, which ensures that all areas inside bubbles are

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excluded from processing by the invention. Imaging characteristics are degraded inside bubbles and tend to introduce false positive objects. Excluding these areas eliminates such false positives.

5       The apparatus of the invention checks that cover slip edges are detected and that all areas outside of the area bounded by cover slip edges are excluded from image processing by the 20x process. Since the apparatus of the invention was not trained to  
10       recognize artifacts outside of the cover slipped area, excluding these areas eliminates possible false positive results.

15       The computer system 540 accumulates slide level 20x results for the slide scoring process. The computer system 540 performs image acquisition and ensures that 20x images passed to the apparatus of the inventions for processing conform to image quality and focus specifications. This ensures that no unexpected imaging characteristics occur.

20       The invention performs three major steps, all of which are described in greater detail below:

25       Step 1     -     For each 20x FOV (20x objective magnification field of view), the algorithm segments potential cell nuclei and detects their cytoplasm boundaries. This step is called image segmentation.

30       Step 2     -     Next, the algorithm measures feature values - such as size, shape, density, and texture - for each potential cell nucleus detected during Step 1. This step is called feature extraction.

      Step 3     -     The algorithm classifies each detected

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5                    object in an FOV using the extracted  
                    feature values obtained in Step 2.  
                    This step is called object  
                    classification. Classification rules  
                    are defined and derived during  
                    algorithm training.

10                   In addition to the object classification, other  
                    measures are made during the classification process  
                    which characterize the stain of the slide, and measure  
                    the confidence of classification.

                    The single cell identification and classification  
                    system of the invention was trained from a cell  
                    library of training slides.

15                   The apparatus of the invention uses multiple  
                    layers of processing. As image data is processed by  
                    the apparatus of the invention, it passes through  
                    various stages, with each stage applying filters and  
                    classifiers which provide finer and finer  
                    discrimination. The result is that most of the  
20                   clearly normal cells and artifacts are eliminated by  
                    the early stages of the classifier. The objects that  
                    are more difficult to classify are reserved for the  
                    later and more powerful stages of the classifier.

25                   During classifier development, the computer  
                    system 540 provides the invention with an image and  
                    allocates space for storing the features calculated on  
                    each object and the results of the apparatus of the  
                    invention. The apparatus of the invention identifies  
                    the potential nuclei in the image, computes features  
30                   for each object, creates results, and stores the  
                    results in the appropriate location.

                    During classifier development, the apparatus of  
                    the invention calculates and stores over 100 features  
                    associate with each object to be entered into the

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object classifier training database. Additionally, the apparatus of the invention stores object truth information provided by expert cytologists for each object in the training database. Developers use  
5 statistical feature analysis methods to select features of utility for classifier design. Once classifiers have been designed and implemented, the apparatus of the invention calculates the selected features and uses them to generate classification  
10 results, confidence values, and stain measures.

Refer now to Figure 2 which shows the item decomposition steps of the invention. In one embodiment of the invention, the computer system 540 processes a 20x magnification field of view FOV.  
15 Steps 10, 12, 14 and 18 are functions that apply to all objects in the image. Steps 20, 22, 24 and 26 are performed only if certain conditions are met. For example, stain evaluation 20 takes place only on objects that are classified as intermediate cells.

20 The first processing step is image segmentation 10 that identifies objects of interest, or potential cell nuclei, and prepares a mask 15 to identify the nucleus and cytoplasm boundaries of the objects.

Features are then calculated 12 using the  
25 original image 11, and the mask 15. The features are calculated in feature calculation step 12 for each object as identified by image segmentation 10. Features are calculated only for objects that are at least ten pixels away from the edge of the image 11.  
30 The feature values computed for objects that are closer to the edge of the image 11 are corrupted because some of the morphological features need more object area to be calculated accurately.

Based on the feature calculation step 12, each  
35 object is classified in classification step 14 as a

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normal cell, an abnormal cell, or an artifact. At various stages throughout the classification process, several other measurements are made dependent on the classification results of the objects:

- 5     ◦ The stain evaluation step 20 measures stain related features on any object that has been identified as an intermediate cell.
- An SIL atypicality process 22 measures the confidence of objects that were classified as  
10     potentially abnormal.
- A robustness process 24 refers to the segmentation and classification. The robustness process 24 measures identified objects that are susceptible to poor classification results  
15     because they are poorly segmented or their feature values lie close to a decision boundary in a classifier.
- A miscellaneous measurements process 26 includes  
20     histograms of confidences from the classifiers, histograms of the stain density of objects classified as abnormal, or proximity measurements of multiple abnormal objects in one image.

The results of the above processes are summarized in step 18. The numbers of objects classified as  
25     normal, abnormal, or artifact at each classification stage are counted, and the results from each of the other measures are totaled. These results are returned to the system where they are added to the results of the other processed images. In total,  
30     these form the results of the entire slide.

The 20x magnification images are obtained at Pixel size of 0.55 x 0.55 microns. The computer 540 stores the address of the memory where the features computed for the objects in the FOV will be stored.

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The computer also stores the address of the memory location where the results structure resides. This memory will be filled with the results of the invention.

- 5       The computer system 540 outputs the following set of data for each field of view:

SEGMENTATION FEATURES

Four features are reported that characterize the segmentation of the image.

- 10       SEGMENTED OBJECT COUNT

The number of objects that were segmented in the FOV. This number may be different from the number classified since objects that are too close to the edge of the FOV are not classified.

- 15       OBJECT COUNTS OF INITIAL BOX FILTER

The number of objects rejected by each of the five stages of the initial box filter.

OBJECT COUNTS OF STAGE1 CLASSIFIER

- 20       The number of objects classified as normal, abnormal, or artifact by Stage1's box classifier, and the number classified as normal, abnormal, or artifact at the end of the Stage1 classifier. (Six numbers are recorded: three for the results of the Stage1 box classifier, and three for the results of the Stage1 classifier.)

- 25       OBJECT COUNTS OF STAGE2 CLASSIFIER

- 30       The number of objects classified as normal, abnormal, or artifact by Stage2's box classifier, and the number classified as normal, abnormal, or artifact at the end of the Stage2 classifier. (Six numbers are recorded: three for the results of the Stage2 box classifier and three for the results of the Stage2 classifier.)

OBJECT COUNTS OF STAGE3 CLASSIFIER

- 35       The number of objects classified as normal,

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abnormal, or artifact by Stage3's box classifier, and the number classified as normal, abnormal, or artifact at the end of the Stage3 classifier. (Six numbers are recorded: three for the results of the Stage3 box classifier and three for the results of the Stage3 classifier.)

OBJECT COUNT OF STAGE4 CLASSIFIER

The number of objects classified as abnormal by the Stage4 classifier.

OBJECT COUNTS OF PLOIDY CLASSIFIER

Two values are computed: the number of objects classified as abnormal by the first stage of the Ploidy classifier and the number of objects classified as highly abnormal by the second stage of the Ploidy classifier.

OBJECT COUNTS OF STAGE4 + PLOIDY CLASSIFIER

Two values are computed: The number of objects classified as abnormal by the Stage4 classifier that were also classified as abnormal by the first stage of the Ploidy classifier, and the number of objects classified as abnormal by the Stage4 classifier that were also classified highly abnormal by the second stage of the Ploidy classifier.

STAGE2/STAGE3/STAGE4/PLOIDY ALARM CONFIDENCE HISTOGRAM

Histograms for the alarm confidence of the Stage2, Stage3, Stage4, and Ploidy alarms detected in an FOV.

STAGE2/STAGE3 ALARM COUNT HISTOGRAM

Two histograms for the alarm count histogram of the Stage2 and Stage3 alarms detected in an FOV.

STAGE2/STAGE3 ALARM IOD HISTOGRAM

Histograms for the Integrated Optical Density (IOD) of objects classified as abnormal by Stage2 and Stage3 in an FOV.

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## INTERMEDIATE CELL IOD-SIZE SCATTERGRAMS

Two IOD vs. size scattergrams of the normal intermediate cells detected in the FOV.

## INTERMEDIATE CELL STAIN FEATURES

5 Six features are accumulated for each object classified as an intermediate cell. These features are all stain related and are used as reference values in the slide level classification algorithms.

## 10 CONTEXTUAL STAGE1 ALARM

Number of Stage1 alarms within a 200 pixel radius of a Stage2 alarm in the same FOV.

## CONTEXTUAL STAGE2 ALARM

15 Number of Stage2 alarms located within a 200 pixel radius of a Stage3 alarm in the same FOV.

## ESTIMATED CELL COUNT

An estimate of the number of squamous cells present in the image.

## ATYPICALITY INDEX

20 An 8x8 array of confidences for all objects sent to the atypicality classifier.

## SEGMENTATION ROBUSTNESS AND CLASSIFICATION DECISIVENESS

25 A set of confidence measures that an object was correctly segmented and classified. This information is available for Stage2 and Stage3 alarms.

## SINGLE CELL ADDON FEATURES

30 A set of eight features for each object classified as a Stage3 alarm. This information will be used in conjunction with slide reference features to gauge the confidence of the Stage3 alarms.

Prior to 20x magnification processing an FOV selection and integration process is performed at a 4x



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magnification scan of the slide to determine the likelihood that each FOV contains abnormal cells. Next, the computer system 540 acquires the FOVs in descending order: from higher likelihood of abnormal cells to lower likelihood.

Image segmentation 10 converts gray scale image data into a binary image of object masks. These masks represent a group of pixels associated with a potential cell nucleus. Using these masks, processing can be concentrated on regions of interest rather than on individual pixels, and the features that are computed characterize the potential nucleus.

The image segmentation process 10 is based on mathematical morphology functions and label propagation operations. It takes advantage of the power of nonlinear processing techniques based on set theoretic concepts of shape and size, which are directly related to the criteria used by humans to classify cells. In addition, constraints that are application specific are incorporated into the segmentation processes of the invention; these include object shape, size, dark and bright object boundaries, background density, and nuclear/cytoplasmic relationships. The incorporation of application-specific constraints into the image segmentation 10 process is a unique feature of the AutoPap® 300 System's processing strategy.

Refer now to Figure 3A which shows the image segmentation process 10 of the invention in more detail. The image segmentation process is described in a U.S. Patent application entitled "Method for Identifying Objects Using Data Processing Techniques" by Shih-Jong James Lee. For each image 29, the image segmentation process 10 creates a mask which uniquely identifies the size, shape and location of every

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object in an FOV. There are three steps involved in image segmentation 10 after the 20x image data 29 is received in 20x imaging step 28: contrast enhancement 30, image thresholding 32, and object refinement 34.

5        During contrast enhancement 30 the apparatus of the invention first enhances, or normalizes, the contrast between potential objects of interest and their backgrounds: bright areas become brighter and dark areas become darker. This phase of processing  
10        creates an enhanced image 31. During image thresholding 32 a threshold test identifies objects of interest and creates a threshold image 33. The threshold image 33 is applied to the enhanced image 31 to generate three binary mask images. These binary  
15        mask images are further refined and combined by an object refinement process 34 to identify the size, shape, and location of objects. The contrast enhancement process 30 increases the contrast between  
20        pixels that represent the object of interest and pixels that represent the background.

Refer now to Figure 3B which shows the contrast enhancement process 30 first normalizes the image background 36 by pixel averaging. The contrast enhanced image 31 is derived from the difference  
25        between the original image 29 and the normalized background 40 computed in enhanced object image transformation step 44. As part of the image contrast enhancement process 30, each object in the field of view undergoes a threshold test 38 using threshold  
30        data 42 to determine whether the brightness of the object lies within a predetermined range. The contrast enhancement process stops at step 47.

At this point, the apparatus of the invention begins to differentiate artifacts from cells so that  
35        artifacts are eliminated from further analysis. The

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apparatus of the invention provides a range of predetermined values for several characteristics, including but not limited to brightness, size and shape of nucleus, cytoplasm and background, of the objects of interest. Objects whose characteristics do not lie within the range of these values are assumed to be artifacts and excluded from further classification.

The brightness of an image is provided by histogram functions shown in Figures 3C and 3D respectively, which determines how many pixels within a gray scale FOV have a certain image intensity. Ideally, the histogram is a curve 48 having three peaks, as shown in the upper histogram in Figure 3C. The three peaks correspond to three brightness levels usually found in the images: the background, the cytoplasm, and the nuclei. If the number of pixels of each brightness level were plotted as a histogram, the largest, brightest peak would be the background since this usually makes up the largest portion of the image 29. The medium brightness peak would correspond to the area of cytoplasm, and the darkest and shortest peak would correspond to the cell nuclei.

This ideal representation rarely occurs since overlapped cells and cytoplasm tend to distort the results of the histogram as shown in the lower histogram 50 in Figure 3D. To reduce the impact of overlapping cells on brightness calculations, the apparatus of the invention applies morphological functions, such as repeated dilations and erosions, to remove overlapped objects from the image before the histogram is calculated.

Referring again to Figure 3A, in addition to the contrast enhanced image 31, a threshold image 33 is generated by a morphological processing sequence. A

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threshold test 32 is then performed on the enhanced image using the threshold image 33 to produce a binary image. The threshold test compares each pixel's value to the threshold image pixel value. The apparatus of  
5 the invention then identifies as an object pixel any pixel in the enhanced image that has an intensity greater than the corresponding pixel of the threshold value.

The threshold image is combined with two  
10 predetermined offset values to generate three threshold images 135, 137 and 139. The first offset is subtracted from each gray scale pixel value of the original threshold image 33 to create a low threshold image. The second offset value is added to each gray  
15 scale pixel value of the threshold image to create a high threshold image. Each of these images - medium threshold, which is the original threshold image, low threshold, and high threshold - are separately combined with the enhanced image to provide three  
20 binary threshold images: a low threshold binary image 35; a medium threshold binary image 37; and a high threshold binary image 39.

Refer now to Figure 3E where the three binary threshold images are refined, beginning with the  
25 medium threshold binary image 37. The medium threshold binary image 37 is refined by eliminating holes and detecting the dark edges 52 of the objects of interest in the enhanced image. Dark edges 54 are linked using a small morphological closing and opening  
30 sequence to fill in holes. Dark edges are detected by determining where there is a variation in intensity between a pixel and its neighboring pixels. Thereafter, boundaries of an edge are detected 56 and identified as a true dark edge mask. The medium  
35 threshold binary image 37 is then combined in a set

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union 58 with the edge boundary detected image 56 to create a dark edge incorporated image 74.

As illustrated in Figure 3F, bright edges 64 of the original image are then excluded from the medium threshold binary image 37. The bright edges of the enhanced image are detected in a manner similar to dark edge detection. The boundary of the dark edge incorporated image 74 is detected and combined with the bright edge enhanced image 64 in a set intersection operation 68. The results are subtracted 70 from the dark edge incorporated image 74 to create a bright edge excluded image 72. The medium threshold binary image 37 is now represented by the bright edge excluded image 72.

Refer to Figures 3G, 3H and 3I which show that Objects 80 from the bright edge excluded image 72 are completed by filling any holes 82 that remain. Holes 82 can be filled without the side effect of connecting nearby objects. Small holes 82 are detected and then added to the original objects 80. To further refine the medium threshold binary image 37, the bright edge excluded image 72 is inverted (black becomes white and vice versa). Objects that are larger than a predetermined size are identified and excluded from the image by a connected component analysis operation. The remaining image is then added to the original image, which provides the completed medium threshold binary mask that fills the holes 82.

To complete the medium threshold binary image 37, connected objects that may not have been separated using the bright edge detection process of Figure 3F are separated. To do so, objects in the medium threshold binary mask 37 are eroded by a predetermined amount and then dilated by a second predetermined amount. The amount of erosion exceeds the amount of

- 20 -

dilation so that objects after dilation are smaller than before erosion. This separates connected objects.

5 A morphological closing residue operation is applied to determine separation boundaries. A separation boundary is subtracted from the hole-filled image to create an overlap object separated binary image. To ensure that no objects have been lost in this process, the overlap object separated image is  
10 dilated to generate an object mask. Small objects not included in the object mask are combined in a set union with the object separation image to provide an object recovered image.

Referring again to Figure 3A, in the last step,  
15 the high and low threshold binary images are combined with the object recovered image (the refined medium threshold binary image) to create final object masks 41, 43 and 45. All objects identified in the high threshold binary image 39 are added to the refined  
20 medium threshold binary image 37 using a set union operation. The resulting mask is eroded by a small amount and dilated by a large amount, so that all objects are connected to a single object. This mask is combined with the low threshold binary mask 35.  
25 Objects in the low threshold binary mask 35 that are not in close proximity to objects in the medium threshold binary mask 37 are added to the image. These objects are added to the refined medium threshold image 43 to create the finished mask. A  
30 connected components labeling procedure removes small or oddly shaped objects and assigns a unique label to each remaining connected object.

The segmented image 15 is used by the feature extraction process 12 to derive the features for each  
35 object. The features computed are characteristic

- 21 -

measures of the object such as size, shape, density, and texture. These measurements are input to the classifiers 14 and allow the apparatus of the invention to discriminate among normal cells, potentially abnormal cells, and artifacts. The features are defined below.

The object classification process 14 consists of a series of classifiers that are grouped in stages. Each stage takes potentially abnormal objects from the previous stage and refines the classification result further using sets of new features to improve the accuracy of classification. At any stage, objects that are classified as normal or artifact are not classified further.

Now refer to Figure 4A which shows the classifier process of the invention. Initial Box Filter classifiers 90 discards obvious artifacts. The data then proceeds through classification stage1, stage2, and stage3, classifiers 92, 94, 96 and ends with the Stage4 and Ploidy classifiers 98, 100.

The purpose of the Initial Box Filter classifier 90 is to identify objects that are obviously not cell nuclei, using as few features as possible, features that preferably are not difficult to compute. Only the features required for classifications are computed at this point. This saves processing time over the whole slide. The initial box filter 90 comprises five separate classifiers designed to identify various types of artifacts. The classifiers operate in series as shown in Figure 4B

As an object passes through the initial box filter, it is tested by each classifier shown in Figure 4B. If it is classified as an artifact, the object classification 14 is final and the object is not sent to the other classifiers. If it is not, the

- 22 -

object goes to the next classifier in the series. If an object is not classified as an artifact by any of 5 classifiers 102, 104, 106, 108 and 110, it will go to the Stage1 classifier 92.

5        Input to the initial box filter 90 comprises a set of feature measurements for each object segmented. The output comprises the following:

- 10        ◦ The number of objects classified as artifact by each of the classifiers, which results in five numbers.
- 15        ◦ The Stage1, Stage2, and Stage3 classification codes for each object classified as an artifact.
- An "active" flag that indicates whether the object has a final classification. If the object is classified as an artifact, it is not active anymore and will not be sent to other classifiers.

20        The initial box filter 90 uses 15 features, which are listed in the following table, for artifact rejection. Each classifier within the initial box filter 90 uses a subset of these 15 features. The features are grouped by their properties.

	<u>Feature type</u>	<u>Feature name(s)</u>
	Condensed Feature	condensed_area_percent
25	Context Texture Feature	big_blur_ave
	Contrast Feature	nc_contrast_orig
	Density Features	mean_orig_2 normalized_mean_od_r3 integrated_density_orig nuc_bright_sm
30	Nucleus/Cytoplasm Texture Contrast Feature	nuc_edge_5_5_sm



## Shape Features

Size Feature

perimeter

```
sd_orig2
nuc_blur_sd
nuc_edge_9_mag
```

15      Box1 102

Box2 104

Artifact Filter for Unfocused Objects and Polies#1 106

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- 24 -

```

      OR
      nuc_edge_5_5_sm > (-1.57 * compactness + 28.59
    )
5  then
    the object is an artifact.

```

#### Artifact Filter for Graphite#2 108

```

else if
  nc_contrast_orig > ( -4.162 *
10  normalized_mean_od_r3 + 615.96 )
  then
    the object is an artifact.

```

#### Artifact Filter for Cytoplasm#3 110

```

else if
  integrated_density_orig < ( 433933.2 *
15  nuc_bright_sm - 335429.8 )
  then
    the object is an artifact.
  else
20  continue the classification process with the
    Stage 1 Box Filter.

```

Up to 40% of objects that are artifacts are identified and eliminated from further processing during the initial box filter 90 processing. This step retains about 99% of cells, both normal and potentially abnormal, and passes them to Stage1 92 for further processing.

Objects that are not classified as artifacts by the classifiers of the initial box filter 90 are passed to Stage1 92, which comprises of a box filter classifier and two binary decision tree classifiers as show in Figure 4C. The Stage1 box filter 92 is used to discard objects that are obviously artifacts or normal cells, using new features which were not available to the initial box filter 90. The binary decision trees then attempt to identify the abnormal cells using a more complex decision process.

The box filter 112 identifies normal cells and

- 25 -

artifacts: the classification of these objects is final. Objects not classified as normal or artifact are sent to Classifier#1 114 which classifies the object as either normal or abnormal. If an object is

5 classified as abnormal, it is sent to Classifier#2 116, where it is classified as either artifact or abnormal. Those objects classified as abnormal by Classifier#2 116 are sent to Stage2 92. Any objects classified as artifact by any of the classifiers in

10 Stage1 92 are not sent to other classifiers.

The input to Stage1 92 comprises of a set of feature measurements for each object not classified as an artifact by the box filters 90. The output comprises the following:

- 15    ◦ The numbers of objects classified as normal, abnormal, and artifact by the Stage1 box classifier, 3 numbers.
- The numbers of objects which were classified as normal, abnormal or artifact at the end of the
- 20       Stage1 classifier 92.
- An "active" flag that indicates whether the object has a final classification. If the object has been classified as an artifact, it is not active anymore and is not sent to other
- 25       classifiers.

The features that are used by each of the Stage1 classifiers 92 are listed in the following tables. They are categorized by their properties.

#### Stage1 Box Filter 112

30	<u>Feature type</u>	<u>Feature name(s)</u>
	Condensed Features	condensed_count condensed_area_percent condensed_compactness

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	Context Density Feature	mean_background
	Context Texture Features	small_blur_ave big_blur_sd sm_blur_sd
5	Contrast Feature	edge_contrast_orig
	Density Feature	integrated_density_od
	Nucleus/Cytoplasm Relation Feature	nc_score_r4
	Shape Feature	compactness
10	Texture Feature	texture_correlation3

# Stagel, Classifier#1 114

	Feature type	Feature name(s)
	Condensed Feature	condensed_count
15	Context Texture Features	big_blur_ave small_edge_9_9 big_edge_5_mag big_edge_9_9 sm_blur_sd
	Contrast Feature	edge_contrast_orig
20	Density Feature	autothresh_enh
	Nucleus/Cytoplasm Relation Features	mod_N_C_ratio cell_nc_ratio nc_score_alt_r3
25	Nucleus/Cytoplasm Texture Contrast Feature	nuc_edge_2_mag_big
	Shape Features	compactness2 density_0_1 inertia_2_ratio

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5	Texture Features	cooc_inertia_4_0 sd_orig nonuniform_run nuc_edge_2_mag nuc_blur_sk sd_enh2 edge_density_r3 cooc_homo_1_0
Stagel, Classifier#2 116		
10	<u>Feature type</u>	<u>Feature name(s)</u>
	Context Density Feature	big_bright
	Context Texture Features	big_edge_2_dir big_edge_9_9
	Contrast Feature	edge_contrast_orig
15	Density Features	mod_nuc_IOD_sm
	integrated_density_orig2	mod_nuc_OD_sm
	normalized_integrated_od	normalized_mean_od
20	Nucleus/Cytoplasm Relation Features	nc_score_r4 cell_semi_isolated mod_N_C_ratio
25	Nucleus/Cytoplasm Texture Contrast Features	nuc_edge_9_mag_sm, nuc_edge_9_9_big
	Shape Feature	area_inner_edge
	Size Feature	perimeter
30	Texture Features	edge_density_r3 nuc_blur_ave
	below_autothresh_enh2	cooc_energy_4_0 cooc_entropy_1_135 nuc_edge_2_dir cooc_corr_1_90 texture_inertia3
35		

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The decision rules used in each classifier are defined as follows:

**Box Filter 112**

```
5  if ( integrated_density_od <= 17275.5 AND
      sm_blur_ave <= 4.98465 AND
      edge_contrast_orig <= -42.023
    )
10 then the object is normal

    else if (
      condensed_count <= 3.5 AND
      compactness <= 10.6828 AND
      sm_blur_ave <= 3.0453 AND
15 integrated_density_od <= 19925 AND
      condensed_area_percent > 0.0884
    )
    then the object is an artifact

20 else if (
      condensed_count <= 3.5 AND
      compactness > 10.6828 AND
      condensed_compactness <= 19.5789
    )
25 then the object is an artifact

    else if (
      integrated_density_od <= 22374 AND
      big_blur_sd <= 3.92333 AND
30 sm_blur_sd <= 1.89516
    )
    then the object is normal

    else if (
35 integrated_density_od <= 22374 AND
      big_blur_sd <= 3.92333 AND
      sm_blur_sd > 1.89516 AND
      nc_score_r4 <= 0.36755 AND
      texture_correlation3 <= 0.7534 AND
40 mean_background > 226.66
    )
    then the object is normal

    else if (
45 integrated_density_od <= 22374 AND
```

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```

big_blur_sd <= 3.92333      AND
sm_blur_sd > 1.89516      AND
nc_score_r4 <= 0.36755    AND
texture_correlation3 > 0.7534
5      )
      then
        the object is normal

      else if (
10      integrated_density_od <= 10957.5 AND
        big_blur_sd <= 3.92333      AND
        sm_blur_sd > 1.89516      AND
        nc_score_r4 > 0.36755
      )
15      then
        the object is normal

      else
        the object continues the classification process
        in Stage1, Classifier1.

```

#### Stage1, Classifier#1 114

20        This classifier is a binary decision tree that  
 uses a linear feature combination at each node to  
 separate normal cells from abnormal cells. The  
 features described in the previous tables make up the  
 linear combination. The features are sent to each  
 25    node of the tree. The importance of each feature at  
 each of the nodes may be different and was determined  
 during the training process.

#### Stage1, Classifier#2 116

30        This classifier is a binary decision tree that  
 uses a linear feature combination at each node to  
 separate artifacts from abnormal cells. The features  
 that make up the tree are listed in a previous table.

35        A significant proportion of the objects  
 classified as abnormal by Stage1 92 are normal cells  
 and artifacts. Stage2 94 attempts to remove these,  
 leaving a purer set of abnormal cells. Stage2 94  
 comprises a box filter 118, which discards objects  
 that are obviously artifacts or normal cells, and two

- 30 -

binary decision trees shown in Figure 4D.

5 The objects classified as abnormal by Stage1 92 enter Stage2 94. The box filter 118 identifies normal cells and artifacts; the classification of these objects is final. Objects not classified as normal or artifact are sent to Classifier#1 120, which classifies the object as either normal or abnormal. If an object is classified as abnormal, it is sent to Classifier#2 122, where it is classified as either artifact or abnormal. Those objects classified as abnormal by Classifier#2 122 are sent to Stage3 96. Any objects classified as normal or artifact by one of the classifiers in Stage2 94 are not sent to other classifiers.

15 The input to Stage2 94 comprises of a set of feature measurements for each object classified as abnormal by Stage1. The output comprises the following:

- 20     o The numbers of objects classified as normal, abnormal, and artifact by the box filter (3 numbers)
- o The numbers of objects which were classified as normal, abnormal or artifact at the end of the Stage2 94 classifier.
- 25     o An "active" flag, which indicates whether the object a final classification. (If it has been classified as artifact or normal it is not active anymore, and will not be sent to other classifiers.)

### 30     **Features Required by the Stage2 94 Classifiers**

The features that are used by each of the Stage2 94 classifiers are listed in the following tables. They are categorized by feature properties.



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## Stage2 94 Box Filter

	<u>Feature type</u>	<u>Feature name(s)</u>
	Condensed Features	condensed_avg_area condensed_compactness
5	Context Density Features	mean_background
	Context Texture Features	sm_blur_sd big_blur_ave sm_blur_ave
	Contrast Feature	nc_contrast_orig
10	Density Features	integrated_density_od integrated_density_od2 normalized_integrated _od_r3
15	Shape Features	compactness shape_score
	Texture Features	nuc_blur_sd texture_inertia4 texture_range4 edge_density_r3
20	Stage2 94, Classifier 1	
	<u>Feature type</u>	<u>Feature name(s)</u>
25	Context Texture Features	sm_blur_ave big_edge_2_dir big_edge_5_mag big_blur_ave big_edge_9_9 big_edge_3_3
	Density Feature	min_od
	Shape Feature	sbx (secondary box test)
30	Size Features	area_inner_edge area nuclear_max perimeter2
35	Texture Features	nuc_blur_ave nuc_blur_sk

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## Stage2 94, Classifier 2

Feature type	Feature name(s)
Condensed Feature	condensed_count
5	Context Density Features
	mean_background mean_outer_od
	Contrast Features
	edge_contrast_orig nc_contrast_orig
	Density Features
	nuc_bright_big mod_nuc_OD_big
10	Shape Features
	compactness2 density_0_1
	Texture Features
15	nuc_edge_9_mag nuc_blur_ave sd_orig2 nuc_blur_sd nuc_edge_2_mag

The Stage2 94 classifier comprises of a box filter and two binary decision trees as shown in Figure 4D. The decision rules used in each classifier are defined as follows:

## Box Filter 118

```

if (
  condensed_avg_area <= 9.4722 AND
  mean_background > 235.182
)
then
  the object is normal

else if (
  condensed_avg_area > 9.4722 AND
  condensed_compactness <= 30.8997 AND
  nuc_blur_sd <= 5.96505 AND
  mean_background <= 233.45 AND
  compactness > 10.4627 AND
  texture_inertia4 <= 0.3763
)
then
  the object is normal

```

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```

5      else if (
          integrated_density_od <= 30253      AND
          condensed_compactness <= 22.0611    AND
          sm_blur_sd <= 6.51617              AND
          shape_score <= 38.8071             AND
          texture_range4 <= 72.5             AND
          integrated_density_od > 15558.5
        )
10     then
        the object is an artifact

    else if (
          integrated_density_od <= 26781.5    AND
          edge_density_r3 <= 0.29495         AND
          mean_background > 233.526
15     )
    then
        the object is an artifact

    else if (
20     integrated_density_od2 <= 23461        AND
          normalized_integrated_od_r3 <= 11176.7 AND
          big_blur_ave <= 5.0609            AND
          nc_contrast_orig > 37.1756        AND
          sm_blur_ave <= 3.0411
25     )
    then
        the object is normal

    else
        continue the classification process with Stage2
        94, Classifier#1 120

30  Stage2 Classifier#1 120
```

This classifier is a binary decision tree that uses a linear feature combination at each node to separate normal cells from abnormal cells. The features used in the tree are listed in a previous table.

#### 35 Stage2 Classifier#2 122

This classifier is a binary decision tree that uses a linear feature combination at each node to separate artifacts from abnormal cells. The features used in the tree are listed in a previous table.

40 A portion of the objects classified as abnormal

- 34 -

cells by the Stage2 94 classifier are normal cells and artifacts; therefore, the stage3 96 classifier tries to remove those, leaving a purer set of abnormal cells. A box filter discards objects that are obviously artifacts or normal cells. The box filter is followed by a binary decision tree shown in Figure 4E.

The objects classified as abnormal by Stage2 94 enter stage3 96. The box filter 124 identifies normal cells and artifacts: the classification of these objects is final. Objects not classified as normal or artifact are sent to the classifier 128, which classifies the object as either normal/artifact or abnormal. If an object is classified as abnormal, it is sent to both stage4 98 and the Ploidy classifiers. Any objects classified as normal or artifact by one of the classifiers in stage3 96 are not sent to other classifiers.

Input to stage3 96 comprises of a set of feature measurements for each object classified as abnormal by Stage2 94. Outputs comprise the following:

- The numbers of objects classified as normal, abnormal, and artifact by the box filter, 3 numbers.
- The number of objects classified as normal, abnormal or artifact at the end of the stage3 96 classifier.
- An "active" flag that indicates whether the object has a final classification. If an object has been classified as a normal or artifact, it is not active anymore and will not be sent to other classifiers.

- 35 -

The features that are used by each of the stage3 96 classifiers are listed in the following tables. They are categorized by feature properties.

**Stage3 Box Filter 124**

5	<u>Feature type</u>	<u>Feature name(s)</u>
	Condensed Feature	condensed_area_percent
	Context Density Features	mean_background mean_outer_od
	Context Distance Feature	cytoplasm_max
10	Context Texture Features	big_blur_sk big_blur_ave big_edge_2_dir small_blur_sd
	Density Feature	integrated_density_od
15	Nucleus/Cytoplasm Relation Feature	cell_semi_isolated
	Shape Features	shape_score density_0_1
20	Size Features	perimeter area
	Texture Features	nonuniform_gray sd_enh nuc_blur_sd texture_range

**25 Stage3 Classifier 128**

	<u>Feature type</u>	<u>Feature name(s)</u>
	Condensed Feature	condensed_compactness
	Context Density Features	mean_outer_od mean_background mean_outer_od_r3
30	Context Texture Features	big_blur_ave big_edge_5_mag sm_edge_9_9

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Density Feature	min_od
Shape Feature	sbx
Texture Features	nuc_edge_2_mag
	cooc_correlation_1_0
	cooc_inertia_2_0
5	nonuniform_gray

The stage3 96 classifier is composed of a box filter and a binary decision tree. The decision rules used in each classifier are as follows:

```

10  Box Filter 124
    if (
        perimeter <= 54.5          AND
        mean_background <= 225.265 AND
        big_blur_sk > 1.33969     AND
15  mean_background <= 214.015
    )
    then
        the object is an artifact

    else if (
20  nonuniform_gray <= 44.5557    AND
        big_blur_ave > 2.91694    AND
        area <= 333.5             AND
        sd_enh > 11.7779          AND
25  nuc_blur_sd > 3.53022        AND
        cytoplasm_max <= 11.5
    )
    then
        the object is an artifact

    else if (
30  nonuniform_gray <= 35.9632    AND
        mean_background <= 225.199 AND
        integrated_density_od <= 31257.5 AND
        texture_range <= 76.5    AND
35  condensed_area_percent <= 0.10055
    )
    then
        the object is an artifact

```

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```

5      else if (
          nonuniform_gray <= 44.4472      AND
          mean_background <= 226.63      AND
          integrated_density_od <= 32322.5      AND
          cell_semi_isolated > 0.5
        )
      then
        the object is an artifact

10     else if (
          nonuniform_gray <= 44.4472      AND
          mean_background <= 226.63      AND
          integrated_density_od <= 32322.5      AND
          cell_semi_isolated <= 0.5      AND
          shape_score <= 69.4799      AND
15         texture_range > 75.5
        )
      then
        the object is an artifact

    if the object was just classified as an artifact:
20    (
        if
          big_edge_2_dir <= 0.3891
        then
          the object is abnormal

25        else if (
          big_edge_2_dir <= 0.683815      AND
          cytoplasm_max <= 22.5      AND
          mean_background <= 223.051      AND
          sm_blur_sd <= 4.41098      AND
30          mean_outer_od <= 38.6805
        )
        then
          the object is abnormal

        else if (
35          big_edge_2_dir <= 0.683815      AND
          density_0_1 > 27.5
        )
        then
          the object is abnormal

40        else if (
          area > 337.5      AND
          mean_background > 223.66
        )
45        then
          the object is abnormal
    )
  )
```

- 38 -

if the object was classified as abnormal  
then continue the classification process with the  
5 stage3 96 Classifier.

### Stage3 Classifier 128

This classifier is a binary decision tree that  
uses a linear feature combination at each node to  
separate normal cells and artifacts from abnormal  
10 cells. The features are listed in a previous table.

The main purpose of Stage1-Stage3 is to separate  
the populations of normal cells and artifacts from the  
abnormal cells. To accomplish this, the decision  
boundaries 136 of the classifiers were chosen to  
15 minimize misclassification for both populations as  
shown, for example, in Figure 4F.

The number of normal cells and artifacts on a  
given slide are far greater than the number of  
abnormal cells, and although the misclassification  
20 rate for those objects is far lower than it is for the  
abnormal cells, the population of objects classified  
as abnormal by the end of the stage3 96 classifier  
still contain some normal cells and artifacts

For example: assume that the misclassification  
25 rate for normal cells is 0.1%, and 10% for abnormal  
cells. If a slide contains 20 abnormal cells and  
10,000 normal/artifact objects, the number of objects  
classified as abnormal would be  $0.001 \times 10,000$  or 10  
normal/artifact objects, and  $20 \times .9$  or 18 abnormal  
30 objects. The noise in the number of abnormal objects  
detected at the end of the stage3 96 classifier makes  
it difficult to recognize abnormal slides.

The stage4 98 classifier uses a different  
decision making process to remove the last remaining



- 39 -

normal/artifact objects from the abnormal population. Stage4 98 takes the population existing after stage3 96 and identifies the clearly abnormal population with a minimum misclassification of the normal cells or artifacts. To do this, a higher number of the abnormal cells are missed than was acceptable in the earlier stages, but the objects that are classified as abnormal do not have normal cells and artifacts mixed in. The decision boundary 138 drawn for the stage4 98 classifier is shown in Figure 4G.

Stage4 is made up of two classifiers. The first classifier was trained with data from stage3 96 alarms. A linear combination of features was developed that best separated the normal/artifact and abnormal classes. A threshold was set as shown in Figure 4G that produced a class containing purely abnormal cells 130 and a class 134 containing a mix of abnormal, normal, and artifacts.

The second classifier was trained using the data that was not classified as abnormal by the first classifier. A linear combination of features was developed that best separated the normal/artifact and abnormal classes. This second classifier is used to recover some of the abnormal cells lost by the first classifier.

The input to stage4 98 comprises of a set of feature measurements for each object classified as abnormal by stage3 96.

The output comprises of the classification result of any object classified as abnormal by stage4 98.

The features that are used by each of the stage4 98 classifiers are listed in the following table. There are two decision rules that make up the stage4 98 classifier. Each uses a subset of the features listed.

- 40 -

	<u>Feature type</u>	<u>Feature name(s)</u>
	Condensed Features	condensed_compactness
	Context Texture Features	big_blur_ave nuc_blur_sd_sm big_edge_5_mag
5	Density Features	nuc_bright_big normalized_integrated od_r3 normalized_integrated_od
10	Nucleus/Cytoplasm Texture Contrast Features	nuc_edge_9_9_big
	Texture Features	nonuniform_gray texture_range4 below_autothresh_enh2
15	Decision Rules of stage4 98	
	The classifier follows these steps:	
	1.	Create the first linear combination of feature values.
20	2.	If the value of the combination is $\geq$ a threshold, the object is classified as abnormal, otherwise it is classified as normal.
	3.	If the object was classified as normal, create the second linear combination.
25	4.	If the value of this second combination is greater than a threshold, the object is classified as abnormal, otherwise it is classified as normal.

- 41 -

```

combination1 = nonuniform_gray * 2.047321387e-02
                + big_blur_ave * 6.059888005e-01
                + nuc_edge_9_9_big * -
5              8.407871425e-02+ big_edge_5_mag *
                -3.132035434e-01 + nuc_blur_sd_sm
                * 7.260803580e-01

```

```

if combination1 ≥ 3.06, the object is abnormal.
if combination1 < 3.06, compute combination2:

```

```

10 combination2 = condensed_compactness *
                2.957029501e-03 + nonuniform_gray
                * 7.682010997e-03 +
                below_autothresh_enh2 *
                3.975555301e-01 + nuc_bright_big
                * - 9.175372124e-01 +
15 normalized_integrated_od_r3 * -
                4.740774966e-05 +
                normalized_integrated_od *
                4.612372868e-05 + texture_range4
                * - 2.707793610e-03

```

```

20 if combination2 ≥ -0.13 the object is abnormal.

```

```

    High grade SIL and cancer cells are frequently
    aneuploid, meaning that they contain multiple copies
    of sets of chromosomes. As a result, the nuclei of
    these abnormal cells stain very dark, and therefore,
25 should be easy to recognize. The ploidy classifier
    100 uses this stain characteristic to identify
    aneuploid cells in the population of cells classified
    as abnormal by the stage3 96 classifier. The presence
    of these abnormal cells may contribute to the final
30 decision as to whether the slide needs to be reviewed
    by a human or not.

```

```

    The ploidy classifier 100 is constructed along

```

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the same lines as the stage4 98 classifier: it is trained on stage3 96 alarms. The difference is that this classifier is trained specifically to separate high grade SIL cells from all other cells; normal, other types of abnormals, or artifacts.

The ploidy classifier 100 is made up of two simple classifiers. The first classifier was trained with data from stage3 96 alarms. A linear combination of features was developed that best separated the normal/artifact and abnormal classes. A threshold was set that produced a class containing purely abnormal cells and a class containing a mix of abnormal, normal, and artifacts.

The second classifier was trained using the data classified as abnormal by the first classifier. A second linear combination was created to separate aneuploid cells from other types of abnormal cells.

The input to the ploidy classifier 100 comprises of a set of feature measurements for each object classified as abnormal by stage3 96.

The output comprises of the classification results of any object classified as abnormal by either classifier in the ploidy classifier 100.

The features used by each of the ploidy classifiers 100 are listed in the following table. There are two decision rules that make up the ploidy classifier 100. Each uses a subset of the features listed.

Feature type	Feature name(s)
Context Texture Features	big_edge_5_mag big_edge_9_9 big_blur_ave
Density Features	normalized_integrated_od nuc_bright_big max_od

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	Density/Texture Features	auto_mean_diff_orig2
	Nucleus/Cytoplasm Relation Features	mod_N_C_ratio nc_score_r4
5	Texture Features	nonuniform_gray texture_range4 nuc_blur_sk

**Ploidy 100 Decision Rules**

The classifier follows these steps:

- 10 1. Create a linear combination of feature values.
2. If the value of the combination is  $\geq$  a threshold, the object is classified as abnormal.
3. If the object was classified as abnormal, create a second linear combination.
- 15 4. If the value of this second combination is greater than a threshold, the object is classified as aneuploid, or highly abnormal.

```

combination1 = nonuniform_gray * 7.005183026e-03
                + auto_mean_diff_orig2 * -
20              1.776645705e-02 + mod_N_C_ratio *
                2.493939400e-01 + nuc_bright_big
                * -9.405089021e-01 +
                normalized_integrated_od * -
25              2.770500259e-06 + big_blur_ave *
                1.802701652e-01 + big_edge_5_mag
                * -8.586113900e-02 + big_edge_9_9
                * -1.906895824e-02 + nuc_blur_sk
                * -1.124482527e-01 + max_od * -
                1.787280198e-03;

```

30 if combination1  $\geq$  -0.090, the object is classified as abnormal.

```

combination2 = big_blur_ave * 2.055980563e-01 +
                texture_range4 * -1.174426544e-02
                + nc_score_r4 * 9.785660505e-01;

```

35 if combination2  $\geq$  0.63, the object is classified as aneuploid.

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5 The ploidy classifier 100 was trained on the same data set as the stage4 98 classifier: 861 normal cells or artifacts, and 1654 abnormal cells, composed of 725 low grade SIL, and 929 high grade SIL. All objects were classified as abnormal by the stage3 96 classifier.

The first classifier correctly identified 31.6% of the abnormal object, and mistakenly classified 9.4% of the normal cells and artifacts as abnormal.

10 The second classifier was trained on all objects which were classified as abnormal by the first classifier: 81 normal cells or artifacts, 124 low grade SIL cells, and 394 high grade SIL cells. The features were selected to discriminate between low grade and high grade cells, ignoring the normal cells and artifacts. The threshold was set using the low grade, high grade, normal cells and artifacts. It correctly classified 34.3% of the high grade SIL cells, and mistakenly classified 14.3% of the low grade, normal cells or artifacts as abnormal cells. Or, it classified 26.8% of the abnormal cells as high grade SIL, and 30.9% of the normal cells or artifacts as high grade SIL.

25 The purpose of stain evaluation 20 is to evaluate the quality of stain for a slide and to aid in the classification of the slide. The stain evaluation 20 for each FOV is accumulated during the 20x slide scan. This information is used at the end of the slide scan to do the following:

30 Judge the quality of the stain.

If the stain of a slide is too different from that of the slides the apparatus of the inventions were trained on, the performance of the classifier may be affected, causing objects to be misclassified.

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Aid in the classification of the slide.

5 The stain features derived from the intermediate cells may be used to normalize other slide features, such as the density features measured on objects classified as abnormal. This will help verify whether the objects classified as abnormal are true abnormal cells or false alarms.

10 Refer again to Figures 2 and 4A, the stain evaluation process 20 is composed of a classifier to identify intermediate cells and a set of stain-related features measured for those cells. Intermediate cells were chosen for use in the stain evaluation 20 because they have high prevalence in most slides, they are easily recognized by the segmentation process, and  
15 their stain quality is fairly even over a slide.

The intermediate cell classifier is run early in the process of the invention, before the majority of the normal cells have been removed from consideration by the classifiers. For this reason, the classifier  
20 takes all of the cells classified as normal from the Stage1 box classifier 112 and determines whether the cell is an intermediate cell or not.

The intermediate cell classifier takes all objects identified as normal cells from the Stage1 Box  
25 classifier 112 and determines which are well segmented, isolated intermediate cells. The intermediate cells will be used to measure the quality of staining on the slide, so the classifier to detect them must recognize intermediate cells regardless of  
30 their density. The intermediate cell classifier contains no density features, so it is stain insensitive.

The features used by the intermediate cell classifier are listed in the following table.

- 46 -

	<u>Feature type</u>	<u>Feature name(s)</u>
5	Nucleus/Cytoplasm Relation Features	mod_N_C_ratio nc_score_alt_r4 cell_semi_isolated
	Nuclear Texture Features Context Texture Feature	nuc_blur_ave big_blur_ave
	Nuclear Size Feature	area2
10	Shape Features	compactness area_inner_edge

15 The intermediate cell classifier is composed of two classifiers. The first classifier is designed to find intermediate cells with a very low rate of misclassification for other cell types. It is so stringent, it only classifies a tiny percentage of the intermediate cells on the slide as intermediate cells.

20 To expand the set of cells on which to base the stain measurements, a second classifier was added that accepts more cells such that some small number of cells other than those of intermediate type may be included in the set.

The following are the decision rules for the first and second classifiers:

25 if  
 ( mod\_N\_C\_ratio  $\leq$  0.073325 and  
 nc\_score\_alt\_r4  $\leq$  0.15115 and  
 nuc\_blur\_ave  $>$  4.6846 and  
 big\_blur\_ave  $\leq$  4.5655 and  
 area2  $>$  96.5 and  
 30 cell\_semi\_isolated  $>$  0.5 and  
 compactness  $\leq$  10.2183 )  
 the object is an intermediate cell according to the  
 first classifier;



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```

if
( mod_N_C_ratio ≤ 0.073325 and
nc_score_alt_r4 ≤ 0.15115 and
nuc_blur_ave > 4.6846 and
5 big_blur_ave ≤ 4.5655 and
area2 > 96.5 and
cell_semi_isolated ≤ 0.5 and
area_inner_edge ≤ 138.5 )
the object is an intermediate cell according to the
10 second classifier.

```

The stain score generator 20 takes the objects identified as intermediate squamous cells by the Intermediate Cell classifier, fills in histograms according to cell size and integrated optical density, and records other stain related features of each cell.

The features used by the stain score generator 21 are listed in the following table.

	<u>Feature type</u>	<u>Feature name(s)</u>
20	Nuclear Optical Density Features	integrated_density_od mean_od
	Nuclear Size Feature	area
25	Nucleus/Cytoplasm Relation Feature	nc_contrast_orig edge_contrast_orig
	Nuclear Texture Features	sd_orig2 nuc_blur_ave
30	Cytoplasm Optical Density Features	mean_outer_od_r3

Now refer to Figure 5 which shows an example of a stain histogram 140. The stain histograms 140 are 2-dimensional, with the x-axis representing the size

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of the cell, and the y-axis representing the integrated optical density of the cell. The IOD bins range from 0 (light) to 7 or 9 (dark). The stain histogram for the first classifier has 10 IOD bins while the second has only 8. The size bins range from 0 (large) to 5 (small). There are six stain bins containing the following size cells:

	Size Bin	Size Range
	0	221+
10	1	191 - 220
	2	161 - 190
	3	131 - 160
	4	101 - 130
	5	0 - 100

The bin ranges for the integrated optical densities of the cells from the first classifier are shown in the following table:

	Density Bin	Density Range
	0	4,000 - 6,000
20	1	6,001 - 8,000
	2	8,001 - 10,000
	3	10,001 - 12,000
	4	12,001 - 14,000
	5	14,001 - 16,000
25	6	16,001 - 18,000
	7	18,001 - 20,000
	8	20,001 - 22,000
	9	22,001+

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The bin ranges for the integrated optical densities of the cells from the second classifier are shown in the following table:

	Density Bin	Density Range
5	0	0 - 4,000
	1	4,000 - 8,000
	2	8,001 - 12,000
	3	12,001 - 16,000
	4	16,001 - 20,000
10	5	20,001 - 24,000
	6	24,001 - 28,000
	7	28,001+

Each object in the image identified as an intermediate cell is placed in the size/density histogram according to its area and integrated optical density. The first histogram includes objects classified as intermediate cells by the first classifier. The second histogram includes objects classified as intermediate cells by either the first or second classifier.

The second part of the stain score generator accumulates several stain measurements for the objects classified as intermediate cells by either of the classifiers. The features are:

mean\_od  
sd\_orig2  
nc\_contrast\_orig  
mean\_outer\_od\_r3  
nuc\_blur\_ave  
edge\_contrast\_orig

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For each of these features, two values are returned to the computer system 540:

- 5 (1) The cumulative total of the feature values for all of the intermediate cells. This will be used to compute the mean feature value for all cells identified as intermediate cells over the whole slide.
- 10 (2) The cumulative total of the squared feature values for all of the intermediate cells. This will be used with the mean value to compute the standard deviation of the feature value for all cells identified as intermediate cells over the whole slide.

$$s.d. = \sqrt{(\mu^2) - (u)^2}$$

15 where  $(u)^2$  is the mean value of the feature value squared, and  $(\mu^2)$  is the mean of the squared feature values.

Now refer again to Figure 2, the SIL atypicality index 22 is composed of two measures: (1) an atypicality measure and (2) a probability density process (pdf) measure. The atypicality measure indicates the confidence that the object is truly abnormal. The pdf measure represents how similar this object is to others in the training data set. The combination of these two measures is used to gauge the confidence that an object identified as abnormal by the Stage2 94 Box classifier is truly abnormal. The highest weight is given to detected abnormal objects with high atypicality and pdf measures, the lowest to those with low atypicality and pdf measures.

30 As illustrated in Figure 4A, the atypicality

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index 22 takes all objects left after the Stage2 94 box filter and subjects them to a classifier.

The following is a list of the features used by the atypicality index classifier 22:

5	nonuniform_gray
	nuc_edge_2_mag
	compactness2
	condensed_compactness
	texture_correlation3
10	nuc_bright_big
	mean_background
	inertia_2_ratio
	nc_score_alt_r3
	edge_contrast_orig
15	mod_N_C_ratio
	normalized_mean_od_r3
	normalized_mean_od
	sd_orig
	mod_nuc_OD
20	sm_edge_9_9
	big_blur_ave
	big_edge_5_mag
	cooc_inertia_4_0
	min_od
25	big_edge_9_9
	sm_blur_sd
	big_edge_2_dir
	sm_bright
	area_outer_edge
30	area
	nuc_blur_ave
	nuc_blur_sd
	perimeter
	nuc_blur_sd_sm

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The following feature array is composed for the object to be classified:

```
Feature_Array[0] = nonuniform_gray
Feature_Array[1] = nuc_edge_2_mag
5 Feature_Array[2] = compactness2
Feature_Array[3] = condensed_compactness
Feature_Array[4] = texture_correlation3
Feature_Array[5] = nuc_bright_big
Feature_Array[6] = mean_background
10 Feature_Array[7] = inertia_2_ratio
Feature_Array[8] = nc_score_alt_r3
Feature_Array[9] = edge_contrast_orig
Feature_Array[10] = mod_N_C_ratio
Feature_Array[11] = normalized_mean_od_r3
15 Feature_Array[12] = normalized_mean_od
Feature_Array[13] = sd_orig
Feature_Array[14] = mod_nuc_OD
Feature_Array[15] = sm_edge_9_9
Feature_Array[16] = big_blur_ave
20 Feature_Array[17] = big_edge_5_mag
Feature_Array[18] = cooc_inertia_4_0
Feature_Array[19] = min_od
Feature_Array[20] = big_edge_9_9
Feature_Array[21] = sm_blur_sd
25 Feature_Array[22] = big_edge_2_dir
Feature_Array[23] = sm_bright
Feature_Array[24] = area_outer_edge
Feature_Array[25] = cc.area
Feature_Array[26] = nuc_blur_ave
30 Feature_Array[27] = nuc_blur_sd
Feature_Array[28] = perimeter
Feature_Array[29] = nuc_blur_sd_sm
```

The original feature array is used to derive a new feature vector with 14 elements. Each element

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corresponds to an eigenvector of a linear transformation as determined by discriminant analysis on the training data set.

5 The new feature vector is passed to two classifiers which compute an atypicality index 23 and a pdf index 25. The atypicality index 23 indicates the confidence that the object is truly abnormal. The pdf index 25 represents how similar this object is to others in the training data set.

10 Once the two classification results have been calculated, they are used to increment a 2-dimensional array for the two measures. The results returned by each of the classifiers is an integer number between 1 and 8, with 1 being low confidence and 8 high confidence. The array contains the  
15 atypicality index on the vertical axis, and the pdf index on the horizontal axis.

One indication of a classifier's quality is its ability to provide the same classification for an  
20 object in spite of small changes in the appearance or feature measurements of the object. For example, if the object was re-segmented, and the segmentation mask changed so that feature values computed using the segmentation mask changed slightly, the  
25 classification should not change dramatically.

An investigation into the sources of classification non-repeatability was a part of the development of the invention. As a result, it was concluded that there are two major causes of non-repeatable classification comprising object and  
30 presentation effects and decision boundary effects. As the object presentation changes, the segmentation changes, affecting all of the feature measurements, and therefore, the classification.

35 Segmentation robustness indicates the

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variability of the segmentation mask created for an object for each of multiple images of the same object. An object with robust segmentation is one where the segmentation mask correctly matches the nucleus and does not vary from image to image in the case where multiple images are made of the same object.

The decision boundary effects refer to objects that have feature values close to the decision boundaries of the classifier, so small changes in these features are more likely to cause changes in the classification result.

Classification decisiveness refers to the variability in the classification result of an object as a result of its feature values in relation to the decision boundaries of the classifier.

The classification decisiveness measure will be high if the object's features are far from the decision boundary, meaning that the classification result will be repeatable even if the feature values change by small amounts. Two classifiers were created to rank the classification robustness of an object. One measures the classification robustness as affected by the segmentation robustness. The other measures the classification robustness as affected by the classification decisiveness.

The segmentation robustness classifier 24 ranks how prone the object is to variable segmentation and the classification decisiveness classifier 26 ranks the objects in terms of its proximity to a decision boundary in feature space.

Figure 6A illustrates the effect of object presentation on segmentation. The AutoPap® 300 System uses a strobe to illuminate the FOV. As a



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result, slight variations in image brightness occur as subsequent images are captured. Objects that have a very high contrast between the nucleus and cytoplasm, such as the robust object 142 shown in Figure 6A, tend to segment the same even when the image brightness varies. Such objects are considered to have robust segmentation.

Objects that have low contrast, such as the first two non-robust objects 144 and 146, are more likely to segment differently when the image brightness varies; these objects are considered to have non-robust segmentation. Another cause of non-robust segmentation is the close proximity of two objects as is shown in the last non-robust object 148. The segmentation tends to be non-robust because the segmentation process may group the objects.

Robust segmentation and classification accuracy have a direct relationship. Objects with robust segmentation are more likely to have an accurate segmentation mask, and therefore, the classification will be more accurate. Objects with non-robust segmentation are more likely to have inaccurate segmentation masks, and therefore, the classification of the object is unreliable. The segmentation robustness measure is used to identify the objects with possibly unreliable classification results.

Figure 6B illustrates the decision boundary effect. For objects 154 with features in proximity to decision boundaries 150, a small amount of variation in feature values could push objects to the other side of the decision boundary, and the classification result would change. As a result, these objects tend to have non-robust classification

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5 results. On the other hand, objects 152 with features that are far away from the decision boundary 150 are not affected by small changes in feature values and are considered to have more robust classification results.

10 The segmentation robustness measure is a classifier that ranks how prone an object is to variable segmentation. This section provides an example of variable segmentation and describes the segmentation robustness measure.

Variable Segmentation Example:

The invention image segmentation 10 has 11 steps:

- 15 1. Pre-processing
2. Histogram statistics
3. Background normalization
4. Enhanced image generation
5. Thresholding image generation
6. Apply thresholding
- 20 7. Dark edge incorporation
8. Bright edge exclusion
9. Fill holes
10. Object separation and recovery
- 25 11. High threshold inclusion and low value pick up

30 The areas of the segmentation that are most sensitive to small changes in brightness or contrast are steps 7, 8, and 9. Figure 6C illustrates the operation of these three steps, which in some cases can cause the segmentation to be non-robust. Line (a) shows the object 170 to be segmented, which comprises of two objects close together. Line (b) shows the correct segmentation of the object 172, 174, 176, and 178 through the dark edge

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incorporation, bright edge exclusion, and fill holes steps of the segmentation process respectively. Line (C) illustrates a different segmentation scenario for the same object 182, 184, 186 and 188 that would result in an incorrect segmentation of the object.

The dark edge incorporation step (7) attempts to enclose the region covered by the nuclear boundary. The bright edge exclusion step (8) attempts to separate nuclear objects and over-segmented artifacts, and the fill hole step (9) completes the object mask. This process is illustrated correctly in line (B) of Figure 6C. If there is a gap in the dark edge boundary, as illustrated in line (C), the resulting object mask 188 is so different that the object will not be considered as a nucleus. If the object is low contrast or the image brightness changes, the segmentation may shift from the example on line (B) to that on line (C).

The input to the segmentation robustness measure comprises of a set of feature measurements for each object classified as abnormal by the second decision tree classifier of Stage2 94.

The output comprises of a number between 0.0 and 1.0 that indicates the segmentation robustness. Higher values correspond to objects with more robust segmentation.

The features were analyzed to determine those most effective in discriminating between objects with robust and non-robust segmentation. There were only 800 unique objects in the training set. To prevent overtraining the classifier, the number of features that could be used to build a classifier was limited. The features chosen are listed in the

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following table:

Feature type	Feature name(s)
Context Distance Feature	min_distance context_3a context_1b
Context Texture Features	sm_bright sm_edge_9_9
Nuclear Density Feature	mean_od
Nuclear Texture Features	hole_percent

10        This classifier is a binary decision tree that  
 uses a linear feature combination at each node to  
 separate objects with robust segmentation from those  
 with non-robust segmentation. The features  
 described in the following list make up the linear  
 15        combination:

Feature\_Array[0] = mean\_od  
 Feature\_Array[1] = sm\_bright  
 Feature\_Array[2] = sm\_edge\_9\_9  
 Feature\_Array[3] = context\_3a  
 20        Feature\_Array[4] = hole\_percent  
 Feature\_Array[5] = context\_1b  
 Feature\_Array[6] = min\_distance

25        The features that are sent to each node of the  
 tree are identical, but the importance of each  
 feature at each of the nodes may be different; the  
 importance of each feature was determined during the  
 training process.

30        The tree that specifies the decision path is  
 called the Segmentation Robustness Measure  
 Classifier. It defines the importance of each  
 feature at each node and the output classification  
 at each terminal node.

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The classification result is a number between 0.0 and 1.0 indicating a general confidence in the robustness, where 1.0 corresponds to high confidence.

5       The classifier was trained using 2373 objects made up of multiple images of approximately 800 unique objects where 1344 objects were robust and 1029 were non-robust.

10       The performance of the classifier is shown in the following table:

	Robust	Non-Robust
Robust	1128	216
Non-Robust	336	693

15       The vertical axis represents the true robustness of the object, and the horizontal axis represents the classification result. For example, the top row of the table shows the following:

- o 1128 objects with robust segmentation were classified correctly as robust.
- 20 o 216 objects with robust segmentation were classified incorrectly as non-robust.

The classifier correctly identified 77% of the objects as either having robust or non-robust segmentation.

25       The confidence measure is derived from the classification results of the decision tree. Therefore, using the confidence measures should provide approximately the same classification performance as shown in the preceding table.

30       The classification decisiveness measure indicates how close the value of the linear

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combination of features for an object is to the decision boundary of the classifier. The decisiveness measure is calculated from the binary decision trees used in the final classifiers of Stage2 94 and stage3 96 by adding information to the tree to make it a probabilistic tree.

The probabilistic tree assigns probabilities to the left and right classes at each decision node of the binary decision tree based on the proximity of the feature linear combination value to the decision boundary. When the linear combination value is close to the decision boundary, both left and right classes will be assigned a similar low decisiveness value. When the linear combination value is away from the decision boundary, the side of the tree corresponding to the classification decision will have high decisiveness value. The combined probabilities from all the decision nodes are used to predict the repeatability of classification for the object.

A probabilistic Fisher's decision tree (PFDT) is the same as a binary decision tree, with the addition of a probability distribution in each non-terminal node. An object classified by a binary decision tree would follow only one path from the root node to a terminal node. The object classified by the PFDT will have a classification result based on the single path, but the probability of the object ending in each terminal node of the tree is also computed, and the decisiveness is based on those probabilities.

Figures 7A and 7B show how the decisiveness measure is computed. The object is classified by the regular binary decision trees used in Stage2 94 and stage3 96. The trees have been modified as

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follows. At each decision node, a probability is computed based on the distance between the object and the decision boundary.

At the first decision node, these probabilities are shown as  $p_1$  and  $1 - p_1$ . The feature values of the objects which would be entering the classification node are assumed to have a normal distribution 190. This normal distribution is centered over the feature value 194, and the value of  $p_1$  is the area of the normal distribution to the left of the threshold 192. If the features were close to the decision boundary, the values of  $p_1$  and  $1 - p_1$  indicated by area 196 would be approximately equal. As the feature combination value drifts to the left of the decision boundary, the value of  $p_1$  increases. Similar probability values are computed for each decision node of the classification tree as shown in Figure 7B. The probability associated with each classification path, the path from the root node to the terminal node where the classification result is assigned, is the product of the probabilities at each branch of the tree. The probabilities associated with each terminal node is shown in Figure 7B. For example, the probability of the object being classified *class1* in the left most branch is  $p_1 p_2$ . The probability that the object belongs to one class is the sum of the probabilities computed for each terminal node of that class. The decisiveness measure is the difference between the probability that the object belongs to *class1* and the probability that it belongs to *class2*.

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$$\begin{aligned}P_{class1} &= p_1 p_2 + (1 - p_1)(1 - p_3) \\P_{class2} &= p_1(1 - p_2) + (1 - p_1)p_3 \\Decisiveness &= |P_{class1} - P_{class2}|\end{aligned}$$

The invention computes two classification decisiveness measures. The first is for objects classified by the second decision tree classifier of Stage2 94. The second is for objects classified by the decision tree classifier of stage3 96. The classification decisiveness measure is derived as the object is being classified. The output comprises the following:

- o The classification decisiveness measure for the object at Stage2 94 and stage3 96 if the object progressed to the stage3 96 classifier. The decisive measures range from 0.0 to 1.0.
- o The product of the classification confidence and the classification decisiveness measure for the object at Stage2 94 and stage3 96.

The features used for the classification decisiveness measure are the same as those used for the second decision tree of Stage2 94 and decision tree of stage3 96 because the classification decisiveness measure is produced by the decision trees.

The decision rules for the classification decisiveness measure are the same as those used for the second decision tree of Stage2 94 and decision tree of stage3 96 because the classification decisiveness measure is produced by the decision trees.

Refer again to Figure 2, miscellaneous measurements process 26 describes features which are computed during classification stages of the



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invention. They are described here because they can be grouped together and more easily explained than they would be in the individual classification stage descriptions. The following features are described

5 in this part of the disclosure:

Stage2 Confidence Histogram  
Stage3 Confidence Histogram  
Stage4 Confidence Histogram  
Ploidy Confidence Histogram  
10 Stage2 94 IOD histogram  
Stage3 IOD histogram  
Contextual Stage1 Alarms  
Contextual Stage2 94 Alarms  
Addon Feature Information  
15 Estimated Cell Count

#### Confidence Histograms

When objects on a slide are classified as alarms, knowing with what confidence the classifications occurred may help to determine  
20 whether the slide really is abnormal or not. Therefore, the following alarm confidence histograms are computed:

- o Stage2 94
- o Stage3 96
- 25 o Stage4 98

#### Stage2 94

The classifier for Stage2 94, classifier 2 is a binary decision tree. The measure of confidence for each terminal node is the purity of the class at  
30 that node based on the training data used to construct the tree. For example, if a terminal node was determined to have 100 abnormal objects and 50

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normal objects, any object ending in that terminal node would be classified as an abnormal object, and the confidence would be  $(100 + 1) / (150 + 2)$  or 0.664.

- 5       The 10 bin histogram for Stage2 94 confidences is filled according to the following confidence ranges.

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	Confidence Bin	Confidence Range
	0	0.000 - 0.490
	1	0.500 - 0.690
	2	0.700 - 0.790
5	3	0.800 - 0.849
	4	0.850 - 0.874
	5	0.875 - 0.899
	6	0.900 - 0.924
	7	0.925 - 0.949
10	8	0.950 - 0.974
	9	0.975 - 1.000

**Stage3**

The confidence of the stage3 96 classifier is determined in the same manner as the Stage2 94 classifier. The confidence histogram bin ranges are also the same as for the Stage2 94 classifier.

**Stage4**

Figure 8 illustrates how the confidence is computed for the stage4 98 classifier. The classification process is described in the object classification 14 Stage4 98 section. If the object is classified as abnormal at steps 204/203 by the first classifier that uses the feature combination 1 step 202, the probability is computed in step 210 as described below. The object will not go to the second classifier, so the probability for the second classifier is set to 1.0 in step 212, and the final confidence is computed in step 216 as the product of the first and second probabilities. If the object was classified as normal at step 204 and step 201 by

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the first classifier, the probability is computed, and the object goes to the second classifier that uses the feature combination 2 step 206. If the object is classified as abnormal by the second classifier at step 208 and step 205, the probability is computed in step 214 for that classifier, and the final confidence is computed as the product of the first and second probabilities in step 216. If the object is classified as normal by the second classifier, no confidence is reported for the object.

To determine the confidence of the classification results in stage 4 98, the mean and standard deviations of the linear combinations of the normal/artifact and abnormal populations were calculated from the training data. These calculations were done for the feature combination 1 step 202 and feature combination 2 step 206. The results are shown in the following table:

	Feature Combination 1	Feature Combination 2
Normal/Artifact mean	2.55	- 0.258
Normal/Artifact sd	0.348	0.084
Abnormal mean	2.80	-0.207
Abnormal sd	0.403	0.095

Using the means and standard deviations calculated, the normal and abnormal likelihoods are computed for feature combination 1:

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$$\text{normal\_likelihood} = \frac{(\text{object\_value} - \text{norm\_pop\_mean})^2}{\text{Norm\_pop\_sd}}$$

$$\text{abnormal\_likelihood} = \frac{(\text{object\_value} - \text{abnorm\_pop\_mean})^2}{\text{abnorm\_pop\_sd}}$$

Compute the likelihood ratio as:

$$\text{likelihood\_ratio} = \frac{\text{norm\_pop\_sd}}{\text{abnorm\_pop\_sd}} (\exp[0.5(\text{abnorm\_likelihood} - \text{norm\_likelihood})])$$

Normalize the ratio:

$$\text{probl} = \frac{\text{likelihood\_ratio}}{1 + \text{likelihood\_ratio}}$$

If the object is classified as normal by the first classifier and as abnormal by the second classifier, compute the normalized likelihood ratio as described previously using the means and standard deviations from the second feature combination. This value will be prob2. The confidence value of an object classified as abnormal by the stage4 98 classifier is the product of probl and prob2, and should range from 0.0 to 1.0 in value. The confidence value is recorded in a histogram.

The confidence histogram has 12 bins. Bin[0] and Bin[11] are reserved for special cases. If the values computed for combination 1 or combination 2 fall near the boundaries of the values existing in the training set, then a confident classification decision cannot be made about the object. If the feature combination value of the object is at the high end of the boundary, increment bin[11] by 1. If the feature combination value is at the low end, increment bin[0] by 1. The decision rules for these

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cases are stated as follows:

```
if ( combination1 > 4.3 || combination2 > 0.08 )
    stage4 98_prob_hist[11] is incremented.
```

```
if ( combination1 < 1.6 || combination2 < -0.55 )
    stage4 98_prob_hist[0] is incremented.
```

5

If the feature combination values are within the acceptable ranges, the objects confidence is recorded in a histogram with the following bin ranges:

	Confidence Bin	Confidence Range
10	1	0.000 - < 0.500
	2	0.500 - < 0.600
	3	0.600 - < 0.700
	4	0.700 - < 0.750
	5	0.750 - < 0.800
15	6	0.800 - < 0.850
	7	0.850 - < 0.900
	8	0.900 - < 0.950
	9	0.950 - < 0.975
20	10	0.975 - 1.000

Figure 9 illustrates how the confidence is computed for the ploidy classifier 100. The classification process is described in the object classification 14 Ploidy 100 section of this document. The object is classified at step 222. If the object is classified as abnormal, "yes" 221, by the first classifier that uses the feature

25

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combination 1 step 220, the probability is computed in step 224 described below and prob2 is set to 1.0 at step 226. The object is then sent to the second classifier. At step 230, if the object was  
5 classified as abnormal, "yes" 231, by the second classifier that uses the feature combination 2 step 228, the probability is computed for that classifier at step 232, and the final confidence is computed as the product of the first and second probabilities in  
10 step 234. If the object is classified as normal by either the first or the second classifier, no confidence is reported for the object.

To determine the confidence of the classification results in the ploidy classifier 100,  
15 the mean and standard deviations of the linear combinations of the normal and abnormal populations were calculated from the training data. These calculations were done for the feature combination 1 step 220 and the feature combination 2 step 228.  
20 The results are shown in the following table:

	The feature combination 1 step 220	The feature combination 2 step 228
Normal/Artifact mean	2.55	- 0.258
Normal/Artifact sd	0.348	0.084
Abnormal mean	2.80	-0.207
Abnormal sd	0.403	0.095

25 Using the means and standard deviations calculated, the normal and abnormal likelihoods are computed for the feature combination 1 step 220:

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$$\text{normal\_likelihood} = \frac{(\text{object\_value} - \text{norm\_pop\_mean})^2}{\text{Norm\_pop\_sd}}$$

$$\text{abnormal\_likelihood} = \frac{(\text{object\_value} - \text{abnorm\_pop\_mean})^2}{\text{abnorm\_pop\_sd}}$$

Compute the likelihood ratio as:

$$\text{likelihood\_ratio} = \frac{\text{norm\_pop\_sd}}{\text{abnorm\_pop\_sd}} (\exp[0.5(\text{abnorm\_likelihood} - \text{norm\_likelihood})])$$

Normalize the ratio:

$$\text{probl} = \frac{\text{likelihood\_ratio}}{1 + \text{likelihood\_ratio}}$$

5 If it goes to Step2, compute the normalized likelihood ratio as described above using the means and standard deviations from the second feature combination. This value will be prob2. The confidence value of an object classified as abnormal by the ploidy classifier 100 is the product of probl and prob2, and should range from 0.0 to 1.0 in value. The confidence value is recorded in a histogram.

10 The confidence histogram has 12 bins. Bin[0] and Bin[11] are reserved for special cases. If the values computed for combination 1 or combination 2 fall near the boundaries of the values existing in the training set, then a confident classification decision cannot be made about the object. If the feature combination value of the object is at the high end of the boundary, increment bin[11] by 1.

15 If the feature combination value is at the low end, increment bin[0] by 1. The decision rules for these cases are stated as follows.



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```

if ( combination1 < -0.60 || combination2 < -0.30 )
    sil_ploidy_prob_hist[0] is incremented.

```

```

if ( combination1 > 0.35 || combination2 > 1.60 )
    sil_ploidy_prob_hist[11] is incremented.

```

- 5            If the feature combination values are within the acceptable ranges, the objects confidence is recorded in a histogram with the following bin ranges:

	Confidence Bin	Confidence Range
10	1	0.000 - < 0.500
	2	0.500 - < 0.600
	3	0.600 - < 0.700
	4	0.700 - < 0.750
	5	0.750 - < 0.800
15	6	0.800 - < 0.850
	7	0.850 - < 0.900
	8	0.900 - < 0.950
	9	0.950 - < 0.975
	10	0.975 - 1.000

## 20    IOD Histograms

- When objects are classified as alarms, it is useful to know their density. Abnormal cells often have an excess of nuclear materials, causing them to stain more darkly. Comparing the staining of the alarms to the staining of the intermediate cells may help determine the accuracy of the alarms.

### Stage2 94

Each object classified as an abnormal cell by the Stage2 94 classifier is counted in the alarm IOD

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histogram. The ranges of the bins are shown in the following table:

	IOD Bin	Range of Integrated Optical Densities per Bin
5	0	0 - 11,999
	1	12,000 - 13,000
	2	14,000 - 15,999
	3	16,000 - 17,999
	4	18,000 - 19,999
10	5	20,000 - 21,999
	6	22,000 - 23,999
	7	24,000 - 25,999
	8	26,000 - 27,999
	9	28,000 - 29,999
15	10	30,000 - 31,999
	11	32,000 - 33,999
	12	34,000 - 35,999
	13	36,000 - 37,999
	14	38,000 - 39,999
20	15	40,000+

### Stage3

The stage3 96 alarm IOD histogram is the same format as the Stage2 94 histogram. It represents the IOD of each object classified as an abnormal object by the stage3 96 classifier.

### Contextual Alarm Measurements

Abnormal objects tend to form clusters, so it is useful to measure how many alarmed objects are

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close to other alarmed objects. Specifically, the following contextual measurements are made:

- 5      ° Contextual Stage2 94 alarm: the number of Stage1 94 alarms that are close to a Stage2 94 alarm
- ° Contextual Stage3 96 alarm: the number of Stage2 94 alarms that are close to a stage3 96 alarm

10      The distance between alarm objects is the Euclidean distance:

$$\sqrt{\Delta x^2 + \Delta y^2}$$

15      If a stage3 96 alarm is contained in an image, the distance between it and any Stage2 94 alarms is measured. If any are within a distance of 200, they are considered close and are counted in the cluster2 feature. This features value is the number of Stage2 94 alarms found close to stage3 96 alarms. The same applies to Stage1 alarms found close to Stage2 94 alarms for the cluster1 feature.

20      Each object that is close to a higher alarm object is counted only once. For example, if a Stage2 94 alarm is close to two stage3 96 alarms, the value of cluster1 will be only 1.

#### Estimated Cell Count

25      The results of the Stage1 classification are used to estimate the number of squamous cells on the slide.

If we define the following variables,

norm = sil\_stagel\_normal\_count1  
abn = sil\_stagel\_abnormal\_count1  
30      art = sil\_stagel\_artifact\_count1

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the estimated cell count is then computed according to this formula:

$$\begin{aligned}
 \text{Est\_CC} = & 0.91 + 1.44 ( \text{norm} ) + 0.75 ( \text{abn} ) + 0.26 \\
 & ( \text{art} ) \\
 - & 0.0021 ( \text{norm}^2 ) + 0.083 ( \text{abn}^2 ) - 0.0013 \\
 & ( \text{art}^2 ) \\
 - & 0.015 ( \text{norm}^2 ) - 0.043 ( \text{norm} * \text{abn} ) - \\
 & 0.016 ( \text{art} * \text{abn} ) + 0.0016 ( \text{norm} * \text{art} * \\
 & \text{abn} )
 \end{aligned}$$

Process performance has been tracked and validated throughout all stages of classification training. A cross validation method was adapted for performance tracking at each stage, in which training data is randomly divided into five equal sets. A classifier is then trained by four of the five sets and tested on the remaining set. Sets are rotated and the process is repeated until every combination of four sets has been used for testing:

	Training data	Test set
20	sets 1, 2, 3 & 4	5
	sets 2, 3, 4 & 5	1
	sets 3, 4, 5 & 1	2
	sets 4, 5, 1 & 2	3
	sets 5, 1, 2, & 3	4

The classification merit (CM) gain is used to measure the performance of the apparatus of the inventions at each stage. where Sensitivity is the percentage of abnormal cells correctly classified as abnormal, FPR is the

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$$CM = \frac{\text{Sensitivity}}{FPR}$$

false positive rate, or the percentage of normal cells and artifacts incorrectly classified as abnormal cells.

5 The objects that were classified as abnormal in the previous stage continue to a further stage of classification. This stage will refine the classification produced by the previous stage, eliminating objects that were incorrectly classified as abnormal. This increases the CM gain. The goal  
10 for the apparatus of the invention is CM gain=200.

**CM Calculation Example:**

A typical normal slide might contain 1,000 significant objects that are normal cells. The goal for the artifact retention rate is 0.2%

15 A low prevalence abnormal slide might contain the same number of normal cells, along with ten significant single abnormal cells. Of the abnormal slide's ten significant abnormal objects, it is expected that the 4x process can select five objects  
20 for processing by the invention. Object classification 14 that has a 40% abnormal cell sensitivity reduces this number to 2. ( $5 \times 40\% = 2$ ).

$$CM = \frac{40\%}{0.20} = 200$$

25 For process performance, the CM gain is expected to fall within the range of  $200 \pm 10$ , and sensitivity is expected to be within the bounds of  $40 \pm 10$ . Results of cross validated testing for each stage are illustrated in Table 5.1, which shows overall CM gain of 192.63 and overall sensitivity of

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32.4%, each of which fall within the range of our goal.

#### The invention Feature Descriptions

5 This section contains names and descriptions of all features that can be used for object classification 14. Not all features are used by the object classification 14 process. Those features that are used by the invention are listed in feature sets.

10 The feature names are taken from the TwentyXFeatures\_s structure in the AutoPap® 300 software implementation.

15 Items shown in bold face are general descriptions that explain a set of features. Many features are variations of similar measures, so an explanation block may precede a section of similar features.

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	Type	Feature	Description
5	int	label_cc:	A unique numeric label assigned to each segmented object. The object in the upper-left corner is assigned a value of 1. The remaining object are labeled 2, 3, etc. from left to right and top to bottom.
	int	x0:	Upper left x coord. of the corner of the box which contains the object region of interest.
10	int	y0:	Upper left y coord. of the corner of the box which contains the object region of interest.
15		x1:	Lower right x coord. of the corner of the box which contains the object region of interest.
	int	y1:	Lower right y coord. of the corner of the box which contains the object region of interest.
20	float	area:	Number of pixels contained in the labeled region.
	float	sch:	A measure of shape defined as: $x = x1 - x0 + 1$ , $y = y1 - y0 + 1$ , $sch = 100 * abs(x - y) / (x + y)$
	float	sbx:	A measure of shape defined as: $x = x1 - x0 + 1$ , $y = y1 - y0 + 1$ , $sbx = 10 * x * y / area$
25	int	stagel_label:	The classification label assigned to the object by the stagel classifier.

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int        stage2 94\_label: The classification label  
assigned to the object by the stage2 94 classifier.

int        stage3 96\_label: The classification label  
assigned to the object by the stage3 96 classifier.

5        float        area2: Same feature as area except the  
area of interest (labeled region) is first eroded by  
a 3x3 element (1-pixel).

float        area\_inner\_edge: Number of pixels in the  
erosion residue using a 5x5 element on the labeled  
10        image (2-pixel inner band).

float        area\_outer\_edge: Number of pixels in the  
5x5 dilation residue minus a 5x5 closing of the  
labeled image (approx. 2-pixel outer band).

15        float        auto\_mean\_diff\_orig2: autothresh\_orig2 -  
mean\_orig2.

float        auto\_mean\_diff\_enh2 : autothresh\_enh2 -  
mean\_enh2.

20        float        autothresh\_enh: These features are  
computed in the same way as autothresh\_orig except  
the enhanced image is used instead of the original  
image.

25        float        autothresh\_enh2: These features are  
computed in the same way as autothresh\_orig2 except  
the enhanced image is used instead of the original  
image.

float        autothresh\_orig: This computation is based



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on the assumption that original image gray scale values within the nuclear mask are bimodally distributed. This feature is the threshold that maximizes the value of "variance-b" given in equation 18 in the paper by N. Otsu titled "A threshold selection method from gray-level histograms", IEEE trans. on systems, man. and cybernetics, vol. smc-9, no. 1 January, 1979.

float      **autothresh\_orig2**: The same measurement except gray scale values are considered within a nuclear mask that has first been eroded by a 3x3 element (1-pixel)).

float      **below\_autothresh\_enh2**: (count of pixels < autothresh\_enh2) / area2

15      float      **below\_autothresh\_orig2**: (count of pixels < autothresh\_orig2) / area2

float      **compactness**: perimeter \* perimeter / area

float      **compactness2**: perimeter2 \* perimeter2 / area

20      float      **compactness\_alt**: perimeter2 / nuclear\_max

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Type	Feature	Description
<b>Condensed</b>		
		For the condensed features, condensed pixels are those whose optical density value is:
5		$\gt ftCondensedThreshold * mean\_od.$
		$ftCondensedThreshold$ is a global floating point variable that can be modified (default is 1.2).
	float <b>condensed_percent:</b>	Sum of the condensed pixels divided by the total object area.
10	float <b>condensed_area_percent:</b>	The number of condensed pixels divided by the total object area.
	float <b>condensed_ratio:</b>	Average optical density values of the condensed pixels divided by the $mean\_od.$
15	float <b>condensed_count:</b>	The number of components generated from a 4-point connected components routine on the condensed pixels.
	float <b>condensed_avg_area:</b>	The average area (pixel count) of all the of condensed components.
20	float <b>condensed_compactness:</b>	The total number of condensed component boundary pixels squared, divided by the total area of all the condensed components.
	float <b>condensed_distance:</b>	The sum of the squared euclidean distance of each condensed pixel to the
25		center of mass, divided by the area.
	float <b>cytoplasm_max:</b>	The greatest distance transform value of the cytoplasm image within each

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area of interest. This value is found by doing an 8-connect distance transform of the cytoplasm image, and then finding the largest value within the nuclear mask.

5     float     cytoplasm\_max\_alt: The greatest distance transform value of the cytoplasm image within each area of interest. The area of interest for cytoplasm\_max is the labeled image while the area of interest of cytoplasm\_max\_alt is the labeled regions  
10    generated from doing a skiz of the labeled image.

float     density\_0\_1: perimeter\_out - perimeter

float     density\_1\_2: Difference between the '1' bin and '2' bin of the histogram described in perimeter.

15   float     density\_2\_3: Difference between the '2' bin and '3' bin of the histogram described in perimeter

float     density\_3\_4: Difference between the '3' bin and '4' bin of the histogram described in  
20   perimeter.

float     edge\_contrast\_orig: First a gray scale dilation is calculated on the original image using a 5x5 structure element. The gray-scale residue is then computed by subtracting the original image from the dilation .edge\_contrast\_orig is the mean of the  
25   residue in a 2-pixel outer ring minus the mean of the residue in a 2-pixel inner ring (the ring refers to the area of interest -- see area\_outer\_edge).

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- `float`      `integrated_density_enh`: Summation of all gray-scale valued pixels within an area of interest (values taken from enhanced image). Value is summed from the conditional histogram of image.
- 5    `float`      `integrated_density_enh2`: The same measurement as the last one except the area of interest is first eroded by a 3x3 element (1-pixel)).
- 10    `float`      `integrated_density_od`: Summation of all gray-scaled valued pixels within an area of interest (values taken from the od image). The od (optical density) image is generated in this routine using the feature processor to do a look-up table operation. The table of values used can be found in the file `fov_features.c` initialized in the static int array `OdLut`.
- 15    `float`      `integrated_density_od2`: The same measurement as the last one except the area of interest is first eroded by a 3x3 element (1-pixel).
- 20    `float`      `integrated_density_orig`: Summation of all gray-scale valued pixels within an area of interest (values taken from original image). Value is summed from the conditional histogram of image.
- 25    `float`      `integrated_density_orig2`: The same measurement as the last one except the area of interest is first eroded by a 3x3 element (1-pixel).
- `float`      `mean_background`: Calculates the average gray-scale value for pixels not on the cytoplasm mask.

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- float      mean\_enh: Mean of the gray-scale valued pixels within an area of interest .Calculated simultaneously with *integrated\_density\_enh* from the enhanced image.
- 5      float      mean\_enh2: The same measurement as the last one except the area of interest is first eroded by a 3x3 element (1-pixel).
- float      mean\_od: The mean of gray-scale values in the od image within the nuclear mask.
- 10      float      mean\_od2: The same measurement as the last one except the area of interest is first eroded by a 3x3 element (1-pixel).
- float      mean\_orig: Mean of gray-scale valued pixels within an area of interest . Calculated simultaneously with *integrated\_density\_orig* from the original image.
- 15      float      mean\_orig2: The same measurement as mean\_orig except the area of interest is first eroded by a 3x3 element (1-pixel).
- 20      float      mean\_outer\_od: The mean of the optical density image is found in an area produced by finding a 5x5 dilation residue minus a 5x5 closing of the nuclear mask (2-pixel border).
- 25      float      normalized\_integrated\_od: First subtract mean\_outer\_od from each gray-scale value in the od image. This produces the "reduced values". Next find the sum of these reduced values in the area of the nuclear mask.

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- float      **normalized\_integrated\_od2**: The same summation described with the last feature computed in the area of the nuclear mask eroded by a 3x3 element (1-pixel).
- 5      float      **normalized\_mean\_od**: Computed with the reduced values formed during the calculation of *normalized\_integrated\_od* : find the mean of the reduced values in the nuclear mask.
- 10      float      **normalized\_mean\_od2**: Same calculation as *normalized\_mean\_od*, except the nuclear mask is first eroded by a 3x3 structure element (1-pixel).
- float      **nc\_contrast\_orig**: Mean of gray-values in outer ring minus *mean\_orig2*.
- 15      float      **nc\_score**: Nuclear-cytoplasm ratio.  
              *nc\_score* = *nuclear\_max* / *cytoplasm\_max*.
- float      **nc\_score\_alt**: Nuclear-cytoplasm ratio.  
              *nc\_score\_alt* = *nuclear\_max* / *cytoplasm\_max\_alt*
- 20      float      **nuclear\_max**: The greatest 4-connect distance transform value within each labeled region. This is calculated simultaneously with *perimeter* and *compactness* using the distance transform image.
- 25      float      **perimeter**: A very close approximation to the perimeter of a labeled region. It is calculated by doing a 4-connect distance transform, and then a conditional histogram. The '1' bin of each histogram is used as the *perimeter* value.

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float      **perimeter\_out**: The "outside" perimeter of a labeled region. It is calculated by doing a dilation residue of the labeled frame using a 3x3 (1-pixel) element followed by a histogram.

5      float      **perimeter2**: The average of **perimeter** and **perimeter\_out**.

10      float      **region\_dy\_range\_enh**: The bounding box or the region of interest is divided into a 3x3 grid (9 elements). If either side of the bounding box is not evenly divisible by 3, then either the dimension of the center grid or the 2 outer grids are increased by one so that there are an integral number of pixels in each grid space. A mean is computed for the enhanced image in the area in common between the nuclear mask and each grid space. The region's dynamic range is the maximum of the means for each region minus the minimum of the means for each region.

20      float      **sd\_difference**: Difference of the two standard deviations. **sd\_difference** = **sd\_orig** - **sd\_enh**.

float      **sd\_enh**: Standard deviation of pixels in an area of interest. Calculated simultaneously with **integrated\_density\_enh** from the enhanced image.

25      float      **sd\_enh2**: The same measurement **sd\_enh** except the area of interest is first eroded by a 3x3 element (1-pixel)).

float      **sd\_orig**: Standard deviation of pixels in an area of interest. Calculated simultaneously with

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integrated\_density\_orig from the original image.

float      sd\_orig2: The same measurement as sd\_orig one except the area of interest is first eroded by a 3x3 element (1-pixel)).

5      float      shape\_score: Using the 3x3 gridded regions described in the calculation of region\_dy\_range\_enh, the mean grayscale value of pixels in the object mask in each grid is found. Four quantities are computed from those mean values: H, V, Lr, and Rl.

10      For H: Three values are computed as the sum of the means for each row. H is then the maximum row value - minimum row value.

For V: Same as for H, computed on the vertical columns of the grid.

15      For Lr: One value is the sum of the means for the diagonal running from the top left to the bottom right. The other two values are computed as the sum of the three means on either side of this diagonal. The value of Lr is the maximum - minimum value for the three regions.

20      For Rl: Same as Lr, except that the diagonal runs from bottom-left to top-right.

$$\text{Shape\_Score} = \sqrt{v^2 + h^2 + Lr^2 + Rl^2}$$

float      perim\_out\_r3: The "outside" perimeter of a labeled region determined by doing a 4-connect distance transform of the labeled image. The number of '1's in each mask are counted to become this value.

25



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float      **nc\_score\_r3**: The average value of the 8-connect distance transform of the cytoplasm mask is found inside the 3x3 dilation residue of the nuclear mask. Call this value X. The feature is then:  
5       $\text{nuclear\_max} / (X + \text{nuclear\_max})$ .

float      **nc\_score\_alt\_r3**: Using "X" as defined in **nc\_score\_r3**, the feature is:  $\text{area} / (3.14 * X * X)$ .

float      **nc\_score\_r4**: The median value of the 8-connect distance transform of the cytoplasm mask is found inside the 3x3 dilation residue of the nuclear mask. This value is always an integer since the discrete probability density process always crosses 0.5 at the integer values. Call this value Y. The feature is then:  $\text{nuclear\_max} / (Y + \text{nuclear\_max})$ .  
10

float      **nc\_score\_alt\_r4**: Using "Y" as defined in **nc\_score\_r4**, the feature is:  $\text{area} / (3.14 * Y * Y)$ .  
15

float      **mean\_outer\_od\_r3**: The mean value of the optical density image in a 9x9 (4 pixel) dilation residue minus a 9x9 closing of the nuclear mask.  
20      The top and bottom 20% of the histogram are not used in the calculation.

float      **normalized\_mean\_od\_r3**: As in **normalized\_mean\_od** except that the values are reduced by **mean\_outer\_od\_r3**.

float      **normalized\_integrated\_od\_r3**: As in **normalized\_integrated\_od** except that the values are reduced by **mean\_outer\_od\_r3**.  
25

float      **edge\_density\_r3**: A gray-scale dilation

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residue is performed on the original image using a 3x3 element. The feature is the number of pixels > 10 that lie in the 5x5 erosion of the nuclear mask.

### Texture

5        In the following texture features, two global variables can be modified to adjust their calculation. ftOccurrenceDelta is an integer specifying the distance between the middle threshold (mean) and the low threshold, and the middle (mean) and the high threshold. ftOccurrenceOffset is an  
10       integer specifying the number of pixels to "look ahead" or "look down".

      To do texture analysis on adjacent pixels, this number must be 1. To compute the texture features  
15       the "S" or "co-occurrence matrix" is first defined. To compute this matrix, the original image is first thresholded into 4 sets. Currently the thresholds to determine these four sets are as follows, where M is the mean\_orig: x = 1 if  $x < M - 20$ , x = 2 if  $M - 20 \leq x < M$ ,  
20       x = 3 if  $M \leq x < M + 20$ , x = 4 if  $x \geq M + 20$ . The co-occurrence matrix is computed by finding the number of transitions between values in the four sets in a certain direction. Since there are four sets the co-occurrence matrix is 4x4. As an example consider  
25       a pixel of value 1 and its nearest neighbor to the right which also has the same value. For this pixel, the co-occurrence matrix for transitions to the right would therefore increment in the first row-column. Since pixels outside the nuclear mask are not analyzed transitions are not recorded for  
30       the pixels on the edge. Finally, after finding the number of transitions for each type in the co-occurrence matrix each entry is normalized by the total number of transitions. texture\_correlation

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and `texture_inertia` are computed for four directions: east, southeast, south, and southwest.

5     float     `texture_correlation`: The correlation process calculation is described on page 187 of *Computer Vision*, written by Ballard & Brown, Prentice-Hall, 1982. Options 2,3,4 indicate the same analysis, except that instead of occurring in the East direction it occurs in the Southeast, South or Southwest direction.

10    float     `texture_inertia`: Also described in *Computer Vision*, id..

float     `texture_range`: The difference between the maximum and minimum gray-scale value in the original image.

15    float     `texture_correlation2`: As above, direction southeast.

float     `texture_inertia2`: As above, direction southeast.

20    float     `texture_range2`: As above, direction southeast.

float     `texture_correlation3`: As above, direction south.

float     `texture_inertia3`: As above, direction south.

25    float     `texture_range3`: As above, direction south.

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float texture\_correlation4: As above, direction southwest.

float texture\_inertia4: As above, direction southwest.

5 float texture\_range4: As above, direction southwest.

#### COOC

In the following features utilizing the "co-occurrence" or "S" matrix, the matrix is derived from the optical density image. To compute this matrix, the optical density image is first thresholded into six sets evenly divided between the maximum and minimum OD value of the cell's nucleus in question. The S or "co-occurrence matrix" is computed by finding the number of transitions between values in the six sets in a certain direction. Since we have six sets, the co-occurrence matrix is 6x6. As an example, consider a pixel of value 1 and its nearest neighbor to the right, which also has the same value. For this pixel, the co-occurrence matrix for transitions to the right would increment in the first row-column. Since pixels outside the nuclear mask are not analyzed, transitions are not recorded for the pixels on the edge. Finally, after finding the number of transitions for each type in the co-occurrence matrix, each entry is normalized by the total number of transitions. The suffixes on these features indicate the position the neighbor is compared against. They are as follows: \_1\_0 : one pixel to the east. \_2\_0: two pixels to the east. \_4\_0: four pixels to the east. \_1\_45: one pixel

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to the southeast. \_1\_90: one pixel to the south.  
\_1\_135: one pixel to the southwest.

float cooc\_energy\_1\_0: The square root of the  
energy process described in *Computer Vision*, id...  
5 Refer to the COOC description above for an  
explanation of the 1\_0 suffix.

float cooc\_energy\_2\_0: Refer to the COOC  
description above for an explanation of the 2\_0  
suffix.

10 float cooc\_energy\_4\_0: Refer to the COOC  
description above for an explanation of the 4\_0  
suffix.

float cooc\_energy\_1\_45: Refer to the COOC  
description above for an explanation of the 1\_45  
15 suffix.

float cooc\_energy\_1\_90: Refer to the COOC  
description above for an explanation of the 1\_90  
suffix.

float cooc\_energy\_1\_135: Refer to the COOC  
20 description above for an explanation of the 1\_135  
suffix.

float cooc\_entropy\_1\_0: The entropy process  
defined in *Computer Vision*, id.. Refer to the COOC  
description above for an explanation of the 1\_0  
25 suffix.

float cooc\_entropy\_2\_0: Refer to the COOC  
description above for an explanation of the 2\_0

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suffix.

float cooc\_entropy\_4\_0: Refer to the COOC  
description above for an explanation of the 4\_0  
suffix.

5 float cooc\_entropy\_1\_45: Refer to the COOC  
description above for an explanation of the 1\_45  
suffix.

10 float cooc\_entropy\_1\_90: Refer to the COOC  
description above for an explanation of the 1\_90  
suffix.

float cooc\_entropy\_1\_135: Refer to the COOC  
description above for an explanation of the 1\_135  
suffix.

15 float cooc\_inertia\_1\_0: The inertia process  
defined in *Computer Vision*, id..

float cooc\_inertia\_2\_0: Refer to the COOC  
description above for an explanation of the 2\_0  
suffix.

20 float cooc\_inertia\_4\_0: Refer to the COOC  
description above for an explanation of the 4\_0  
suffix.

float cooc\_inertia\_1\_45: Refer to the COOC  
description above for an explanation of the 1\_45  
suffix.

25 float cooc\_inertia\_1\_90: Refer to the COOC  
description above for an explanation of the 1\_90

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suffix.

float      cooc\_inertia\_1\_135: Refer to the COOC  
description above for an explanation of the 1\_135  
suffix.

5      float      cooc\_homo\_1\_0: The homogeneity process  
described in *Computer Vision, id.*. Refer to the  
COOC description above for an explanation of the 1\_0  
suffix.

10      float      cooc\_homo\_2\_0: Refer to the COOC  
description above for an explanation of the 2\_0  
suffix.

float      cooc\_homo\_4\_0: Refer to the COOC  
description above for an explanation of the 4\_0  
suffix.

15      float      cooc\_homo\_1\_45: Refer to the COOC  
description above for an explanation of the 1\_45  
suffix.

20      float      cooc\_homo\_1\_90: Refer to the COOC  
description above for an explanation of the 1\_90  
suffix.

float      cooc\_homo\_1\_135: Refer to the COOC  
description above for an explanation of the 1\_135  
suffix.

25      float      cooc\_corr\_1\_0: The correlation process  
described in *Computer Vision, id.*. Refer to the  
COOC description above for an explanation of the 1\_0  
suffix.

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float      cooc\_corr\_2\_0: Refer to the COOC  
description above for an explanation of the 2\_0  
suffix.

5      float      cooc\_corr\_4\_0: Refer to the COOC  
description above for an explanation of the 4\_0  
suffix.

float      cooc\_corr\_1\_45: Refer to the COOC  
description above for an explanation of the 1\_45  
suffix.

10      float      cooc\_corr\_1\_90: Refer to the COOC  
description above for an explanation of the 1\_90  
suffix.

15      float      cooc\_corr\_1\_135: Refer to the COOC  
description above for an explanation of the 1\_135  
suffix.

#### Run Length

20      The next five features are computed using run  
length features. Similar to the co-occurrence  
features, the optical density image is first  
thresholded into six sets evenly divided between the  
maximum and minimum OD value of the cell's nucleus  
in question. The run length matrix is then computed  
from the lengths and orientations of linearly  
connected pixels of identical gray levels. For  
25      example, the upper left corner of the matrix would  
count the number of pixels of gray level 0 with no  
horizontally adjacent pixels of the same gray value.  
The entry to the right of the upper left corner  
counts the number of pixels of gray level 0 with one  
30      horizontally adjacent pixel of the same gray level.



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**float emphasis\_short:** The number of runs divided by the length of the run squared:

$$\sum_{i=1}^{\# \text{ gray}} \sum_{j=1}^{\# \text{ runs}} \frac{P(i,j)}{j^2}$$

**5**  $p(i,j)$  is the number of runs with gray level  $i$  and length  $j$ . This feature emphasizes short runs, or high texture.

**float emphasis\_long:** The product of the number of runs and the run length squared:

$$\sum_{i=1}^{\# \text{ gray}} \sum_{j=1}^{\# \text{ runs}} j^2 \cdot p(i,j)$$

**10**  $p(i,j)$  is the number of runs with gray level  $i$  and length  $j$ . This feature emphasizes long runs, or low texture.

**float nonuniform\_gray:** The square of the number of runs for each gray level:

$$\sum_{i=1}^{\# \text{ gray}} \left[ \sum_{j=1}^{\# \text{ runs}} p(i,j) \right]^2$$

The process is at a minimum when the runs are equally distributed among gray levels.

**15 float nonuniform\_run:** The square of the number of runs for each run length:

$$\sum_{j=1}^{\# \text{ runs}} \left[ \sum_{i=1}^{\# \text{ gray}} p(i,j) \right]^2$$

This process is at its minimum when the runs are equally distributed in length.

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float      **percentage\_run**: The ratio of the total number of runs to the number of pixels in the nuclear mask:

$$\frac{\sum_{i=1}^{\# \text{ gray}} \sum_{j=1}^{\# \text{ runs}} p(i,j)}{\# \text{ pixels}}$$

5      This feature has a low value when the structure of the object is highly linear.

float      **inertia\_2\_min\_axis**: Minimum axis of the 2nd moment of inertia of the nuclear region normalized by the area in pixels.

10      float      **inertia\_2\_max\_axis**: Maximum axis of the 2nd moment of inertia of the nuclear region normalized by the area in pixels.

float      **inertia\_2\_ratio**:  $\text{inertia\_2\_min\_axis} / \text{inertia\_2\_max\_axis}$ .

15      float      **max\_od**: Maximum optical density value contained in the nuclear region.

float      **min\_od**: Minimum optical density value contained in the nuclear region.

float      **sd\_od**: Standard deviation of the optical density values in the nuclear region.

20      float      **cell\_free\_lying**: This feature can take on two values: 0.0 and 1.0 (1.0 indicates the nucleus is free lying). To determine if a cell is free lying, a connected components is done on the cytoplasm image, filtering out any components smaller than 400

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pixels and larger in size than the integer variable `AlgFreeLyingCytoMax` (default is 20000). If only one nucleus bounding box falls inside the bounding box of a labeled cytoplasm, the nucleus (cell) will be  
5 labeled free lying (1.0), else the nucleus will be labeled 0.0.

`float cell_semi_isolated`: This feature can take on two values: 0.0 and 1.0 (1.0 indicates the nucleus is semi-isolated). A nucleus is determined to be  
10 semi-isolated when the center of its bounding box is a minimum euclidean pixel distance from all other nuclei (center of their bounding boxes). The minimum distance that is used as a threshold is stored in the global floating-point variable  
15 `AlgSemiIsolatedDistanceMin` on the FOV card (default is 50.0). Only nuclei with the `cc.active` field non-zero will be used in distance comparisons; non-active cells will be ignored entirely.

`float cell_cyto_area`: If the cell has been  
20 determined to be free-lying (`cell_free_lying`= 1.0), this number represents the number of pixels in the cytoplasm (value is approximated due to earlier downsampling). If the cell is not free-lying, this number is 0.0.

25 `float cell_nc_ratio`: If the cell has been determined to be free-lying (`cell_free_lying`= 1.0), this number is `cc.area / cell_cyto_area`. If the cell is not free-lying, this number is 0.0.

30 `float cell_centroid_diff`: This feature is used on free-lying cells. The centroid of the cytoplasm is calculated, and the centroid of the nucleus. The

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feature value is the difference between these two centroids.

#### Local Area Context Normalization Features

5       The original image nucleus is assumed to  
contain information not only about the nucleus, but  
also about background matter. The gray level  
recorded at each pixel of the nucleus will be a  
summation of the optical density of all matter in  
10       the vertical column that contains the particular  
nucleus pixel. In other words, if the nucleus is  
located in a cytoplasm which itself is located in a  
mucus stream, the gray level values of the nucleus  
will reflect not only the nuclear matter, but also  
15       the cytoplasm and mucus in which the nucleus lies.  
To try to measure features of the nucleus without  
influence of the surroundings and to measure the  
nucleus surroundings, two regions have been defined  
around the nucleus. Two regions have been defined  
because of a lack of information about how much area  
20       around the nucleus is enough to identify what is  
happening in proximity to the nucleus.

      The two regions are rings around each nucleus.  
The first ring expands 5 pixels out from the nucleus  
(box 7x7 and diamond 4) and is designated as the  
25       "small" ring. The second region expands 15 pixels  
out from the nucleus (box 15x15 and diamond 9) and  
is called the "big" ring.

float       sm\_bright: Average intensity of the pixels  
in the small ring as measured in the original image.

30       float       big\_bright: Average intensity of the  
pixels in the big ring as measured in the original  
image.

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float      nuc\_bright\_sm: Average intensity of the nuclear pixels divided by the average intensity of the pixels in the big ring.

5      float      nuc\_bright\_big: Average intensity of the nuclear pixels divided by the average intensity of the pixels in the small ring.

### 3x3

10      The original image is subtracted from a 3x3 closed version of the original. The resultant image is the 3x3 closing residue of the original. This residue gives some indication as to how many dark objects smaller than a 3x3 area exist in the given region.

15      float      sm\_edge\_3\_3: Average intensity of the 3x3 closing residue in the small ring region.

float      big\_edge\_3\_3: Average intensity of the 3x3 closing residue in the big ring region.

20      float      nuc\_edge\_3\_3\_sm: Average intensity of the 3x3 closing residue in the nuclear region divided by the average intensity of the 3x3 closing residue in the small ring.

25      float      nuc\_edge\_3\_3\_big: Average intensity of the 3x3 closing residue in the nuclear region divided by the average intensity of the 3x3 closing residue in the big ring.

### 5x5

The residue of a 5x5 closing of the original image is done similarly to the 3x3 closing residue

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except that the 3x3 closed image is subtracted from the 5x5 closed image instead of the original. This isolates those objects between 3x3 and 5x5 in size.

5       float       sm\_edge\_5\_5: Average intensity of the 5x5 closing residue in the small ring region.

float       big\_edge\_5\_5: Average intensity of the 5x5 closing residue in the big ring region.

10       float       nuc\_edge\_5\_5\_sm: Average intensity of the 5x5 closing residue in the nuclear region divided by the average intensity of the 5x5 closing residue in the small ring.

15       float       nuc\_edge\_5\_5\_big: Average intensity of the 5x5 closing residue in the nuclear region divided by the average intensity of the 5x5 closing residue in the big ring.

20       9x9  
The residue of a 9x9 closing of the original image is done in the same way as the 5x5 closing residue described above except the 5x5 closing residue is subtracted from the 9x9 residue rather than the 3x3 closing residue.

float       sm\_edge\_9\_9: Average intensity of the 9x9 closing residue in the small ring region.

25       float       big\_edge\_9\_9: Average intensity of the 9x9 closing residue in the big ring region.

float       nuc\_edge\_9\_9\_sm: Average intensity of the 9x9 closing residue in the nuclear region divided by

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the average intensity of the 9x9 closing residue in the small ring.

float      nuc\_edge\_9\_9\_big: Average intensity of the 9x9 closing residue in the nuclear region divided by the average intensity of the 9x9 closing residue in the big ring.

## 2 Mag

To find if an angular component exists as part of the object texture, closing residues are done in the area of interest using horizontal and vertical structuring elements. The information is combined as a magnitude and an angular disparity measure. The first structuring elements used are a 2x1 and 1x2.

float      nuc\_edge\_2\_mag: Magnitude of 2x1 and 1x2 closing residues within the nuclei. Square root of  $((\text{average horizontal residue})^2 + (\text{average vertical residue})^2)$ .

float      sm\_edge\_2\_mag: Magnitude of 2x1 and 1x2 closing residues within the small ring. Square root of  $((\text{average horizontal residue})^2 + (\text{average vertical residue})^2)$ .

float      big\_edge\_2\_mag: Magnitude of 2x1 and 1x2 closing residues within the big ring. Square root of  $((\text{average horizontal residue})^2 + (\text{average vertical residue})^2)$ .

float      nuc\_edge\_2\_mag\_sm:  $\text{nuc\_edge\_2\_mag} / \text{sm\_edge\_2\_mag}$ .

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float      nuc\_edge\_2\_mag\_big: nuc\_edge\_2\_mag /  
big\_edge\_2\_mag.

float      nuc\_edge\_2\_dir: Directional disparity of  
2x1 and 1x2 closing residues within the nuclei.  
5      (average vertical residue) / ( (average horizontal  
residue) + (average vertical residue) ).

float      sm\_edge\_2\_dir: Directional disparity of  
2x1 and 1x2 closing residues in the small ring.  
(average vertical residue) / ( (average horizontal  
10      residue) + (average vertical residue) ).

float      big\_edge\_2\_dir: Directional disparity of  
2x1 and 1x2 closing residues in the big ring.  
(average vertical residue) / ( (average horizontal  
residue) + (average vertical residue) ).

15      float      nuc\_edge\_2\_dir\_sm: nuc\_edge\_2\_dir /  
sm\_edge\_2\_dir.

float      nuc\_edge\_2\_dir\_big: nuc\_edge\_2\_dir /  
big\_edge\_2\_dir.

#### 5 Mag

20      The structuring elements used are a 5x1 and a  
1x5. In this case, the residue is calculated with  
the 2x1 or 1x2 closed images rather than the  
original as for the 2x1 and 1x2 structuring elements  
described previously.

25      float      nuc\_edge\_5\_mag: Magnitude of 5x1 and 1x5  
closing residues within the nuclei. Square root of  
( (average horizontal residue)^2 + (average vertical  
residue)^2 ).



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float      sm\_edge\_5\_mag: Magnitude of 5x1 and 1x5  
closing residues within the small ring. Square root  
of ( (average horizontal residue)^2 + (average  
vertical residue)^2 ).

5      float      big\_edge\_5\_mag: Magnitude of 5x1 and 1x5  
closing residues within the big ring. Square root  
of ( (average horizontal residue)^2 + (average  
vertical residue)^2 ).

10      float      nuc\_edge\_5\_mag\_sm: nuc\_edge\_5\_mag /  
sm\_edge\_5\_mag

float      nuc\_edge\_5\_mag\_big: nuc\_edge\_5\_mag /  
big\_edge\_5\_mag

15      float      nuc\_edge\_5\_dir: Directional disparity of  
5x1 and 1x5 closing residues within the nuclei.  
(average vertical residue) / ( (average horizontal  
residue) + (average vertical residue) ).

20      float      sm\_edge\_5\_dir: Directional disparity of  
5x1 and 1x5 closing residues in the small ring.  
(average vertical residue) / ( (average horizontal  
residue) + (average vertical residue) ).

25      float      big\_edge\_5\_dir: Directional disparity of  
5x1 and 1x5 closing residues in the big ring.  
(average vertical residue) / ( (average horizontal  
residue) + (average vertical residue) ).

float      nuc\_edge\_5\_dir\_sm: nuc\_edge\_5\_dir /  
sm\_edge\_5\_dir

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```
float      nuc_edge_5_dir_big: nuc_edge_5_dir /
big_edge_5_dir
```

### 9 Mag

5       The last of the angular structuring elements used are a 9x1 and 1x9. In this case, the residue is calculated with the 5x1 or 1x5 closed images rather than the 2x1 and 1x2 structuring elements described for the 5x1 and 1x5 elements.

```
10 float      nuc_edge_9_mag: Magnitude of 9x1 and 1x9
closing residues within the nuclei. Square root of
( (average horizontal residue)^2 + (average vertical
residue)^2 ).
```

```
15 float      sm_edge_9_mag: Magnitude of 9x1 and 1x9
closing residues within the small ring. Square root
of ( (average horizontal residue)^2 + (average
vertical residue)^2 ).
```

```
20 float      big_edge_9_mag: Magnitude of 9x1 and 1x9
closing residues within the big ring. Square root
of ( (average horizontal residue)^2 + (average
vertical residue)^2 ).
```

```
float      nuc_edge_9_mag_sm: nuc_edge_9_mag /
sm_edge_9_mag
```

```
float      nuc_edge_9_mag_big: nuc_edge_9_mag /
big_edge_9_mag
```

```
25 float      nuc_edge_9_dir: Directional disparity of
9x1 and 1x9 closing residues within the nuclei.
(average vertical residue) / ( (average horizontal
residue) + (average vertical residue) ).
```

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float      sm\_edge\_9\_dir: Directional disparity of  
9x1 and 1x9 closing residues in the small ring.  
(average vertical residue) / ( (average horizontal  
residue) + (average vertical residue) ).

5      float      big\_edge\_9\_dir: Directional disparity of  
9x1 and 1x9 closing residues in the big ring.  
(average vertical residue) / ( (average horizontal  
residue) + (average vertical residue) ).

10      float      nuc\_edge\_9\_dir\_sm: nuc\_edge\_9\_dir /  
sm\_edge\_9\_dir

float      nuc\_edge\_9\_dir\_big: nuc\_edge\_9\_dir /  
big\_edge\_9\_dir

#### Blur

15      As another measure of texture, the original is  
blurred using a 5x5 binomial filter. A residue is  
created with the absolute magnitude differences  
between the original and the blurred image.

float      nuc\_blur\_ave: Average of blur image over  
label mask.

20      float      nuc\_blur\_sd: Standard deviation of blur  
image over label mask.

float      nuc\_blur\_sk: skewness of blur image over  
label mask.

25      float      nuc\_blur\_ku: kurtosis of blur image over  
label mask.

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float      sm\_blur\_ave: Average of blur image over  
small ring.

float      sm\_blur\_sd: Standard deviation of blur  
image over small ring.

5      float      sm\_blur\_sk: Skewness of blur image over  
small ring.

float      sm\_blur\_ku: Kurtosis of blur image over  
small ring.

10      float      big\_blur\_ave: Average of blur image over  
big ring.

float      big\_blur\_sd: Standard deviation of blur  
image over big ring.

float      big\_blur\_sk: Skewness of blur image over  
big ring.

15      float      big\_blur\_ku: Kurtosis of blur image over  
big ring.

float      nuc\_blur\_ave\_sm: Average of blur residue  
for the nuclei divided by the small ring.

20      float      nuc\_blur\_sd\_sm: Standard deviation of blur  
residue for the nuclei divided by the small ring.

float      nuc\_blur\_sk\_sm: Skew of blur residue for  
the nuclei divided by the small ring.

float      nuc\_blur\_ave\_big: Average of blur residue  
for the nuclei divided by the big ring.

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float      nuc\_blur\_sd\_big: Standard deviation of  
blur residue for the nuclei divided by the big ring.

float      nuc\_blur\_sk\_big: Skew of blur residue for  
the nuclei divided by the big ring.

5      float      mod\_N\_C\_ratio: A ratio between the nuclear  
area and the cytoplasm area is calculated. The  
cytoplasm for each nuclei is determined by taking  
only the cytoplasm area that falls inside of a skiz  
boundary between all nuclei objects. The area of  
10      the cytoplasm is the number of cytoplasm pixels that  
are in the skiz area corresponding to the nuclei of  
interest. The edge of the image is treated as an  
object and therefore creates a skiz boundary.

15      float      mod\_nuc\_OD: The average optical density of  
the nuclei is calculated using floating point  
representations for each pixel optical density  
rather than the integer values as implemented in the  
first version. The optical density values are  
scaled so that a value of 1.2 is given for pixels of  
20      5 or fewer counts and a value of 0.05 for pixel  
values of 245 or greater. The pixel values between  
5 and 245 span the range logarithmically to meet  
each boundary condition.

25      float      mod\_nuc\_IOD: The summation of the optical  
density values for each pixel within the nuclei.

float      mod\_nuc\_OD\_sm: The average optical density  
of the nuclei minus the average optical density of  
the small ring.

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float      mod\_nuc\_OD\_big: The average optical density of the nuclei minus the average optical density of the big ring.

5      float      mod\_nuc\_IOD\_sm: mod\_nuc\_OD\_sm \* number of pixels in the nuclei. Essentially, this is the integrated optical density of the nuclei normalized by the average optical density of the pixels within the small ring around the nuclei.

10      float      mod\_nuc\_IOD\_big: mod\_nuc\_OD\_big \* number of pixels in the nuclei. Same as above, except the average optical density in the big ring around the nuclei is used to normalized the data.

OD\_bin\_\*\_\*

15      These features are the result of placing each pixel in the nuclear mask area in a histogram where each bin represents a range of optical densities. The numbers should be read as 1\_2 = 1.2, 0\_825 = 0.825.

20      The original image is represented as transmission values. These values are converted during the binning process to show equal size bins in terms of optical density which is a log transformation of the transmission. The Histogram bins refer to the histogram of pixels of  
25      transmission values within the nuclear mask.

float      OD\_bin\_1\_2: Sum Histogram bins #0 - 22 / Area of label mask.

float      OD\_bin\_1\_125: Sum Histogram bins #13 / Area of label mask.

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- float OD\_bin\_1\_05: Sum Histogram bins #23 - 26 /  
Area of label mask.
- float OD\_bin\_0\_975: Sum Histogram bins #27 - 29  
/ Area of label mask.
- 5 float OD\_bin\_0\_9: Sum Histogram bins #30 - 34 /  
Area of label mask.
- float OD\_bin\_0\_825: Sum Histogram bins #35 - 39  
/ Area of label mask.
- 10 float OD\_bin\_0\_75: Sum Histogram bins #40 - 45 /  
Area of label mask.
- float OD\_bin\_0\_6 75: Sum Histogram bins #46 - 53  
/ Area of label mask.
- float OD\_bin\_0\_6: Sum Histogram bins #54 - 62 /  
Area of label mask.
- 15 float OD\_bin\_0\_525: Sum Histogram bins #63 - 73  
/ Area of label mask.
- float OD\_bin\_0\_45: Sum Histogram bins #74 - 86 /  
Area of label mask.
- 20 float OD\_bin\_0\_375: Sum Histogram bins #87 - 101  
/ Area of label mask.
- float OD\_bin\_0\_3: Sum Histogram bins #102 - 119  
/ Area of label mask.
- float OD\_bin\_0\_225: Sum Histogram bins #120 -  
142 / Area of label mask.

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float      OD\_bin\_0\_15: Sum Histogram bins #143 -187  
/ Area of label mask.

float      OD\_bin\_0\_075: Sum Histogram bins #188 -  
255 / Area of label mask.

5      float      context\_3a: systemFor this feature, the  
bounding box of the nucleus is expanded by 15 pixels  
on each side. The feature is the ratio of the area  
of other segmented objects which intersect the  
enlarged box to compactness of the box, where the  
10      compactness is defined as the perimeter of the box  
squared divided by the area of the box.

float      hole\_percent: The segmentation is done in  
several steps. At an intermediate step, the nuclear  
mask contains holes which are later filled in to  
15      make the mask solid. This feature is the ratio of  
the area of the holes to the total area of the  
final, solid, mask.

float      context\_1b: For this feature, the bounding  
box of the nucleus is expanded by 5 pixels on each  
20      side. The feature is the ratio of the area of other  
segmented objects which intersect the enlarged box  
to the total area of the enlarged box.

float      min\_distance: The distance to the centroid  
of the nearest object from the centroid of the  
25      current object.

#### The invention Results Descriptions

This section shows all of the results of the  
invention that are written to the results structure  
TwentyXResult, which is contained in alh\_twentyx.h..



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**int high\_count:** Measures dark edge gradient content of the whole original image. This is a measure of how much cellular material may be in the image.

5 **int high\_mean:** The average value of all pixels in an image that have values between 199 and 250. This feature provides some information about an image's background.

**int medium\_threshold:**  $\text{lower\_limit\_0} - \text{lower\_limit\_1}$  where  $\text{lower\_limit\_0}$  is the value of the  $\text{low\_threshold} + 30$ , or 70, whichever is greater.  $\text{lower\_limit\_1}$  is the value of  $\text{high\_mean} - 40$ , or 150, whichever is greater.

15 **int low\_threshold:** The low threshold value is the result of an adaptive threshold calculation for a certain range of pixel intensities in an image during the segmentation process. It gives a measure for how much dark matter there is in an image. If the threshold is low, there is a fair amount of dark matter in the image. If the threshold is high, there are probably few high density objects in the image.

**float time1:** Time variables which may be set during the invention processing.

25 **float time2:** Same as time1

**float time3:** Same as time1

**float time4:** Same as time1

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float      stain\_mean\_od: The cumulative value of mean\_od for all objects identified as intermediate cells.

5      float      stainsq\_mean\_od: The cumulative squared value of mean\_od for all objects identified as intermediate cells.

float      stain\_sd\_orig2: The cumulative value of sd\_orig2 for all objects identified as intermediate cells.

10      float      stainsq\_sd\_orig2: The cumulative squared value of sd\_orig2 for all objects identified as intermediate cells.

15      float      stain\_nc\_contrast\_orig: The cumulative value of nc\_contrast\_orig for all objects identified as intermediate cells.

float      stainsq\_nc\_contrast\_orig: The cumulative squared value of nc\_contrast\_orig for all objects identified as intermediate cells.

20      float      stain\_mean\_outer\_od\_r3: The cumulative value of mean\_outer\_od\_r3 for all objects identified as intermediate cells.

float      stainsq\_mean\_outer\_od\_r3: The cumulative squared value of mean\_outer\_od\_r3 for all objects identified as intermediate cells.

25      float      stain\_nuc\_blur\_ave: The cumulative value of nuc\_blur\_ave for all objects identified as intermediate cells.

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- float      stainsq\_nuc\_blur\_ave: The cumulative squared value of nuc\_blur\_ave for all objects identified as intermediate cells.
- 5 float      stain\_edge\_contrast\_orig: The cumulative value of edge\_contrast\_orig for all objects identified as intermediate cells.
- float      stainsq\_edge\_contrast\_orig: The cumulative squared value of edge\_contrast\_orig for all objects identified as intermediate cells.
- 10 int        intermediate\_hist1[10][6]: Histogram representing the features of all intermediate cells identified by the first classifier. 10 bins for IOD, and 6 for nuclear area.
- 15 int        intermediate\_hist2[8][6]: Histogram representing the features of all intermediate cells identified by the second classifier. 8 bins for IOD, and 6 for nuclear area.
- 20 int        sil\_box1\_artifact\_count: Total number of objects in the image classified as artifacts by the Box1 classifier.
- int        sil\_box2\_artifact\_count: Total number of objects in the image classified as artifacts by the Box2 classifier.
- 25 int        sil\_box3\_artifact\_count: Total number of objects in the image classified as artifacts by the first classifier of the Artifact Filter.

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- int        **sil\_box4\_artifact\_count**: Total number of  
objects in the image classified as artifacts by the  
second classifier of the Artifact Filter.
- 5        int        **sil\_box5\_artifact\_count**: Total number of  
objects in the image classified as artifacts by the  
third classifier of the Artifact Filter.
- int        **conCompCount**: The number of objects  
segmented in the image.
- 10       int        **sil\_stage1\_normal\_count1**: Total number of  
objects classified as normal at the end of the  
Stage1 classifier.
- int        **sil\_stage1\_artifact\_count1**: Total number  
of objects classified as artifact at the end of the  
Stage1 classifier.
- 15       int        **sil\_stage1\_abnormal\_count1**: Total number  
of objects classified as abnormal at the end of the  
Stage1 classifier.
- int        **sil\_stage2\_normal\_count1**: Total number of  
objects classified as normal at the end of the  
20       Stage2 94 classifier.
- int        **sil\_stage2\_artifact\_count1**: Total number  
of objects classified as artifact at the end of the  
Stage2 94 classifier.
- 25       int        **sil\_stage2\_abnormal\_count1**: Total number  
of objects classified as abnormal at the end of the  
Stage2 94 classifier.

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- int        sil\_stage3\_normal\_count1: Total number of  
objects classified as normal at the end of the  
stage3 96 classifier.
- 5        int        sil\_stage3\_artifact\_count1: Total number  
of objects classified as artifact at the end of the  
stage3 96 classifier.
- int        sil\_stage3\_abnormal\_count1: Total number  
of objects classified as abnormal at the end of the  
stage3 96 classifier.
- 10       int        sil\_cluster\_stage2\_count: The number of  
objects classified as abnormal by the Stage2 94  
classifier which are close to abnormal objects from  
the stage3 96 classifier.
- 15       int        sil\_cluster\_stage1\_count: The number of  
objects classified as abnormal by the Stage1  
classifier which are close to abnormal objects from  
the Stage2 94 classifier.
- float       sil\_est\_cellcount: An estimate of the  
number of squamous cells in the image.
- 20       int        sil\_stage2\_alarm\_IOD\_histo[16]: Histogram  
representing the IOD of all objects classified as  
abnormal by the Stage2 94 classifier.
- 25       int        sil\_stage2\_alarm\_conf\_hist[10]: Histogram  
representing the confidence of classification for  
all objects classified as abnormal by the Stage2 94  
classifier.

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int        sil\_stage3\_alarm\_IOD\_histo[16]: Histogram  
representing the IOD of all objects classified as  
abnormal by the stage3 96 classifier.

5        int        sil\_stage3\_alarm\_conf\_hist[10]: Histogram  
representing the confidence of classification for  
all objects classified as abnormal by the stage3 96  
classifier.

10       int        sil\_stagel\_normal\_count2: Total number of  
objects classified as normal by the Stagel Box  
classifier.

15       int        sil\_stagel\_abnormal\_count2: Total number  
of objects classified as abnormal by the Stagel Box  
classifier.

20       int        sil\_pl\_stage2\_normal\_count2: Total number  
of objects classified as normal by the Stage2 94 Box  
classifier.

25       int        sil\_pl\_stage2\_artifact\_count2: Total  
number of objects classified as artifact by the  
Stage2 94 Box classifier.

int        sil\_pl\_stage3\_normal\_count2: Total number  
of objects classified as normal by the stage3 96 Box

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classifier.

int        sil\_p1\_stage3\_abnormal\_count2: Total  
number of objects classified as abnormal by the  
stage3 96 Box classifier.

5        int        sil\_p1\_stage3\_artifact\_count2: Total  
number of objects classified as artifact by the  
stage3 96 Box classifier.

int        sil\_stage4\_alarm\_count: Total number of  
objects classified as abnormal by the stage4 98  
10 classifier.

int        sil\_stage4\_prob\_hist[12]: Histogram  
representing the confidence of classification for  
all objects classified as abnormal by the stage4 98  
classifier.

15        int        sil\_ploidy\_alarm\_count1: Total number of  
objects classified as abnormal by the first ploidy  
classifier 100.

int        sil\_ploidy\_alarm\_count2: Total number of  
objects classified as abnormal by the second ploidy  
20 classifier 100.

int        sil\_ploidy\_prob\_hist[12]: Histogram  
representing the confidence of classification for  
all objects classified as abnormal by the ploidy  
classifier 100.

25        int        sil\_S4\_and\_P1\_count: Total number of  
objects classified as abnormal by both the stage4 98  
and the first ploidy classifier 100.

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int        sil\_S4\_and\_P2\_count: Total number of  
objects classified as abnormal by both the stage4 98  
and the second ploidy classifier 100.

5        int        atypical\_pdf\_index[8][8]: A 2D histogram  
representing two confidence measures of the objects  
classified as abnormal by the Stage2 94 Box  
classifier. Refer to the description of the  
atypicality classifier in this document.

10       int        sil\_seg\_x\_s2\_decisive[4]: A 4 bin  
histogram of the product of the segmentation  
robustness value and the Stage2 94 decisiveness  
value.

15       int        sil\_seg\_x\_s3\_decisive[4]: A 4 bin  
histogram of the product of the segmentation  
robustness value and the stage3 96 decisiveness  
value.

int        sil\_s2\_x\_s3\_decisive[4]: A 4 bin histogram  
of the product of the Stage2 94 decisiveness value  
and the stage3 96 decisiveness value.

20       int        sil\_seg\_x\_s2\_x\_s3\_decisive[4]: A 4 bin  
histogram of the product of the segmentation  
robustness value, the Stage2 94 decisiveness value,  
the stage3 96 decisiveness value.

25       int        sil\_stage2\_dec\_x\_seg[4][4]: A 4x4 array of  
Stage2 94 decisiveness (vertical axis) vs.  
segmentation robustness (horizontal axis).

int        sil\_stage3\_dec\_x\_seg[4][4]: A 4x4 array of  
stage3 96 decisiveness (vertical axis) vs.



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segmentation robustness (horizontal axis).

int        sil\_s3\_x\_s2\_dec\_x\_seg[4][4]: A 4x4 array  
of the product of Stage2 94 and stage3 96  
decisiveness (vertical axis) vs. segmentation  
5        robustness (horizontal axis).

int        sil\_s3\_x\_segrobust\_x\_s2pc[4][4]: A 4x4  
array of the product of segmentation robustness and  
stage3 96 decisiveness (vertical axis) vs. the  
product of Stage2 94 confidence and Stage2 94  
10        decisiveness (horizontal axis).

int        sil\_s3\_x\_segrobust\_x\_s3pc[4][4]: A 4x4  
array of the product of segmentation robustness and  
stage3 96 decisiveness (vertical axis) vs. the  
product of stage3 96 confidence and stage3 96  
15        decisiveness (horizontal axis).

float       sil\_stage3\_ftr, [NUM\_FOV\_ALM],  
[LEN\_FOV\_FTR]:        A set of 8 features for an  
                         object which was classified as  
                         abnormal by the stage3 96  
20                       classifier. NUM\_FOV\_ALM refers  
                         to the number of the alarm as it  
                         was detected in the 20x scan (up  
                         to 50 will have features  
                         recorded). LEN\_FOV\_FTR refers  
25                       to the feature number: 0 - 7

#### Cell Types Recognized by The invention

The invention has been trained to recognize  
single or free lying cell types: normal, potentially  
abnormal, and artifacts that typically appear in  
30        Papanicolaou-stained cervical smears. This section

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lists the cell types that were used to train the invention.

**Normal Single Cells**

- single superficial squamous
- 5 single intermediate squamous
- single squamous metaplastic
- single parabasal squamous
- single endocervical
- single endometrial
- 10 red blood cells

**Abnormal Single Cells**

- single atypical squamous
- single atypical metaplastic
- single atypical endocervical columnar
- 15 single atypical endometrial
- single low grade SIL
- single high grade SIL
- single endocervical columnar dysplasia, well segmented
- 20 single carcinoma in situ, endocervical columnar, well segmented
- single adenocarcinoma, endocervical columnar
- single adenocarcinoma, endometrial
- single adenocarcinoma, metaplastic
- 25 single invasive carcinoma, small cell squamous
- single invasive carcinoma, large cell squamous
- single invasive carcinoma, keratinizing squamous
- single marked repair/reactive squamous
- single marked repair/reactive, endocervical
- 30 single marked repair/reactive, metaplastic
- single herpes
- single histiocyte
- single lymphocyte

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- single slightly enlarged superficial squamous
- single slightly enlarged intermediate squamous
- single slightly enlarged metaplastic squamous
- single slightly enlarged parabasal squamous
- 5 slightly enlarged endocervical

**Artifacts**

- single air dried intermediate cell nucleus
- single air dried metaplastic/parabasal cell nucleus
- single air dried endocervical cell nucleus
- 10 single questionable abnormal cell nucleus
- single over segmented intermediate cell nucleus
- single over segmented metaplastic/parabasal cell nucleus
- single artifact, 1 nucleus over segmented
- 15 artifact, 2 nuclei
- artifact, 3+ nuclei
- single folded cytoplasm
- cytoplasm only
- bare nucleus
- 20 unfocused
- polymorphs (white blood cells)
- graphites
- corn flaking
- mucous
- 25 junk from cover slip
- other junk

- 30 The invention has been described herein in considerable detail in order to comply with the Patent Statutes and to provide those skilled in the art with the information needed to apply the novel principles and to construct and use such specialized components as are required. However, it is to be understood that the invention can be carried out by specifically different equipment and devices, and

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that various modifications, both as to the equipment details and operating procedures, can be accomplished without departing from the scope of the invention itself.

5

What is claimed is:

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## CLAIMS

1. A cell identification apparatus for identifying object types of interest, the apparatus comprising:
  - 5 (a) an image segmenter means (10) for processing at least one image (11) of a biological specimen having a segmented image output;
  - 10 (b) feature calculation means (12) for computing features having at least one feature output; and
  - 15 (c) means for classifying objects (14), connected to receive the at least one feature output, having a classified output where the classified output identifies objects (80) as being object types of interest.
2. The apparatus of claim 1 wherein the feature calculation means (12) comprises an object  
20 feature extractor.
3. The apparatus of claim 1 wherein the feature calculation means (12) comprises a contextual feature extractor.
4. The apparatus of claim 1 wherein the feature  
25 calculation means (12) comprises a whole image feature extractor.
5. The apparatus of claim 1 wherein the objects (80, 82) comprise free-lying cells.
6. The apparatus of claim 1 wherein the objects  
30 (80, 82) comprise non-nuclear overlapped cells.

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7. The apparatus of claim 1 wherein the object types of interest (80, 82) comprise normal cells, abnormal cells or artifacts.
- 5 8. The apparatus of claim 7 wherein the normal cells comprise reference intermediate cells (142).
9. The apparatus of claim 7 wherein the abnormal cells comprise cancerous and precancerous cells.
- 10 10. The apparatus of claim 1 wherein the biological specimen is a specimen prepared by the Papanicolaou method.
11. The apparatus of claim 1 wherein the biological specimen is a gynecological specimen.
- 15 12. The apparatus of claim 1 further comprising a means for accumulating the classified output (18).
13. The apparatus of claim 1 comprising a means for measuring a stain (92) of at least one type of object (142, 144, 146, 148).
- 20 14. The apparatus of claim 13 wherein the at least one type of object (80) comprises reference intermediate cells (142).
- 15 25 15. The apparatus of claim 1 further comprising a means for measuring a classification confidence (216) for a set of objects (80, 82) classified

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as being object types of interest (80, 82).

16. The apparatus of claim 1 further comprising a means for measuring a reliability of object segmentation (24).

5 17. The apparatus of claim 1 further comprising a means for measuring repeatability of classification results (Figure 7B).

18. A free-lying cell segmenter (10) comprising:

- 10 (a) a means for acquiring at least one image (28) of a biological specimen having an image output (29);
- 15 (b) a means for creating a contrast enhanced image (30) having an enhanced image output (31) wherein the means for creating a contrast enhanced image (30) is connected to receive the at least one image (29);
- 20 (c) a means for image thresholding (32) having an image threshold output (33) wherein the means for image thresholding (32) is connected to receive the contrast enhanced image (31); and
- 25 (d) a means for object refinement (34) having a refined object output wherein the means for object refinement (34) is connected to receive the thresholded image output (33).

19. A feature classifier for performing a plurality of stages of feature extraction (12) and object classification (14) on cells in a biological specimen comprising:

- 30 (a) means for acquiring at least one image (28) of a biological specimen;

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- (b) an initial stage classifier means (90) for determining whether objects (80, 82) in the at least one image are object types of interest and other objects; and
- 5 (c) a sequence of object classifiers (92, 94, 96, 98, 100) wherein each object classifier has an object type of interest input, an object type of interest output and an other object type output, and
- 10 wherein the object type of interest output is connected to the object type of interest input of a next classifier (92, 94, 96, 98, 100) in the sequence.
20. The apparatus of claim 19 further comprising:
- 15 (a) an initial box filter means (90) for determining whether objects (80, 82) are normal, potentially abnormal or artifacts;
- (b) a stage 1 classifier means (92) for processing the normal and potentially
- 20 abnormal objects into a potentially abnormal, artifact or normal object;
- (c) a stage 2 classifier means (94) for determining whether the potentially
- 25 abnormal objects from the stage 1 classifier (92) are potentially abnormal, artifact or normal;
- (d) a stage 3 classifier (96) for determining whether the potentially abnormal objects
- 30 from the stage 2 classifier (94) are potentially abnormal or are normal and artifact objects;
- (e) a stage 4 classifier (98) for determining whether the potential abnormal objects from the stage 3 classifier (96) are



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potentially abnormal or normal artifacts.

21. The apparatus of claim 19 further comprising a  
diagnostic classifier means (100) for  
determining whether the objects of interest  
5 (80, 82) from a final classifier (96) in the  
sequence of classifiers are low grade squamous  
intraepithelial lesions, potential high grade  
squamous intraepithelial lesions, cancerous  
lesions and normal artifacts.
- 10 22. The apparatus of claim 19 wherein the object  
types of interest (80, 82) comprise normal  
cells (142), abnormal cells and artifacts.
23. The apparatus of claim 22 wherein the normal  
cells (142) comprise reference intermediate  
15 cells.
24. The apparatus of claim 22 wherein the abnormal  
cells comprise cancerous and precancerous  
cells.
25. The apparatus of claim 19 wherein the  
20 biological specimen is a specimen prepared by  
the Papanicolaou method.
26. The apparatus of claim 19 wherein the  
biological specimen is a gynecological  
specimen.
- 25 27. The apparatus of claim 19 further comprising a  
means for computing (94) an atypicality index  
(22).

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28. The apparatus of claim 20 wherein the initial box filter (90) further comprises a filter selected from the group consisting of a dark object filter (104), an unfocused object filter (106), a polymorphonuclear leukocytes filter, a graphite filter (108), and a cytoplasm filter (110).
29. The apparatus of claim 19 wherein at least one of the classifiers in the sequence of object classifiers (90, 92, 94, 96, 98, 100) comprises a box filter (90).
30. The apparatus of claim 19 wherein at least one of the classifiers in the sequence of object classifiers (90, 92, 94, 96, 98, 100) comprises a decision tree classifier (Figure 7B).
31. The apparatus of claim 19 wherein at least one of the classifiers in the sequence of object classifiers (90, 92, 94, 96, 98, 100) comprises a binary decision tree classifier (Figure 7B).
32. The apparatus of claim 19 wherein at least one of the classifiers in the sequence of object classifiers (90, 92, 94, 96, 98, 100) comprises a fuzzy classifier.
33. The apparatus of claim 19 wherein at least one of the classifiers in the sequence of object classifiers (90, 92, 94, 96, 98, 100) comprises a non-parametric classifier.
34. The apparatus of claim 19 wherein at least one of the classifiers (Figure 8) in the sequence

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of object classifiers (90, 92, 94, 96, 98, 100) further comprises means for measuring confidence (216).

- 5           35. The apparatus of claim 20 wherein the stage 4 classifier (98) comprises:
- (a) a feature combination classifier (202) for classifying objects as normal or abnormal;
  - (b) a means for computing a probability (210) of abnormal objects being abnormal;
  - 10       (c) a means for combining (206) a second set of features to determine whether the object is classified as normal or abnormal;
  - (d) a means for computing a probability (214) of the object being abnormal; and
  - 15       (e) a means for combining (216) the first probability (210) and the second probability (214) to produce a final confidence factor.
- 20       36. The apparatus of claim 21 wherein the diagnostic classifier, being a ploidy classifier, further comprises:
- (a) means for computing a probability that the object is abnormal (224);
  - 25       (b) means for computing whether the object is classified as aneuploid (230);
  - (c) means for computing a probability that the object is aneuploid (232); and
  - (d) means for combining the first probability and the second probability to provide a
  - 30       final confidence (234).
37. The apparatus of claim 19 further including a

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plurality of computer processors (540) wherein the plurality of computer processors (540) perform multilayered processing.

- 5      38. An apparatus for computing a stain score from a biological specimen comprising:
- 10            (a) means for acquiring at least one image (28) of a biological specimen;
- (b) means for classifying objects (14) that are object types of interest (142, 144, 146, 148) in the at least one image (28), wherein the means for classifying objects (14) provides a classified object output;
- 15            (c) means for measuring stain feature values (92) from the objects of interest (142, 144, 146, 148), connected to the classified object output, wherein the means for measuring stain feature values (92) has a stain feature value output; and
- 20            (d) means for accumulating stain feature values (18) connected to the stain feature value output, and wherein the means for accumulating stain feature values (18) generates a stain score output (21).
- 25      39. The apparatus of claim 38 wherein the stain feature values (21) comprise a density of an object of interest (142, 144, 146, 148).
- 30      40. The apparatus of claim 38 wherein the stain feature values (21) comprise texture of the object of interest (142, 144, 146, 148).
41. The apparatus of claim 38 wherein the stain feature (21) comprises a difference in at least

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one feature of the objects of interest (142, 144, 146, 148) and at least one feature measurement of the background of the objects of interest.

5

42. An apparatus for measuring the repeatability of classification for a biological specimen comprising:

10

(a) means for acquiring at least one image (10) of a biological specimen;

(b) means, connected to receive the at least one image, for computing object features (12) having an object features output;

15

(c) means for classifying objects (14) connected to the object features output, wherein the means for classifying objects provides a classified object output;

20

(d) means for estimating a classification repeatability (Figure 7B) of object types, connected to the classified object output and object features output, wherein the means for estimating (Figure 7B) has a classification repeatability output.

25

43. The apparatus of claim 42 wherein the means for estimating the classification repeatability (Figure 7B) further comprising feature distance measuring means for computing a distance from a feature value to a classification boundary (Figure 6B) of the objects of interest.

30

44. An apparatus for measuring the reliability for object segmentation of a biological specimen comprising:

(a) means for acquiring at least one image

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- (28) of a biological specimen having an image output (29);
- 5 (b) means for image segmentation (10) connected to the image output (29) to detect objects of interest (80, 82), wherein the means for image segmentation (10) has a segmented object output;
- 10 (c) means for feature extraction (12) connected to the segmented object output, wherein the means for feature extraction (12) has a segmentation reliability feature output (24);
- 15 (d) means for classification of objects (14) connected to the segmentation reliability feature output (24) having a classified output (216), where the classified output (216) comprises a measure of the reliability of the segmented object output.
- 20 45. A feature classification process for performing a plurality of stages of feature extraction and object classification on cells in a biological specimen comprising:
- 25 (a) an initial box filter means (90) for determining whether objects (80, 82) are normal and potentially abnormal or artifacts;
- 30 (b) a stage 1 classifier means (92) for processing the normal and potentially abnormal objects into a potentially abnormal, artifact or normal object;
- (c) a stage 2 classifier means (94) for determining whether the potentially abnormal objects from the stage 1

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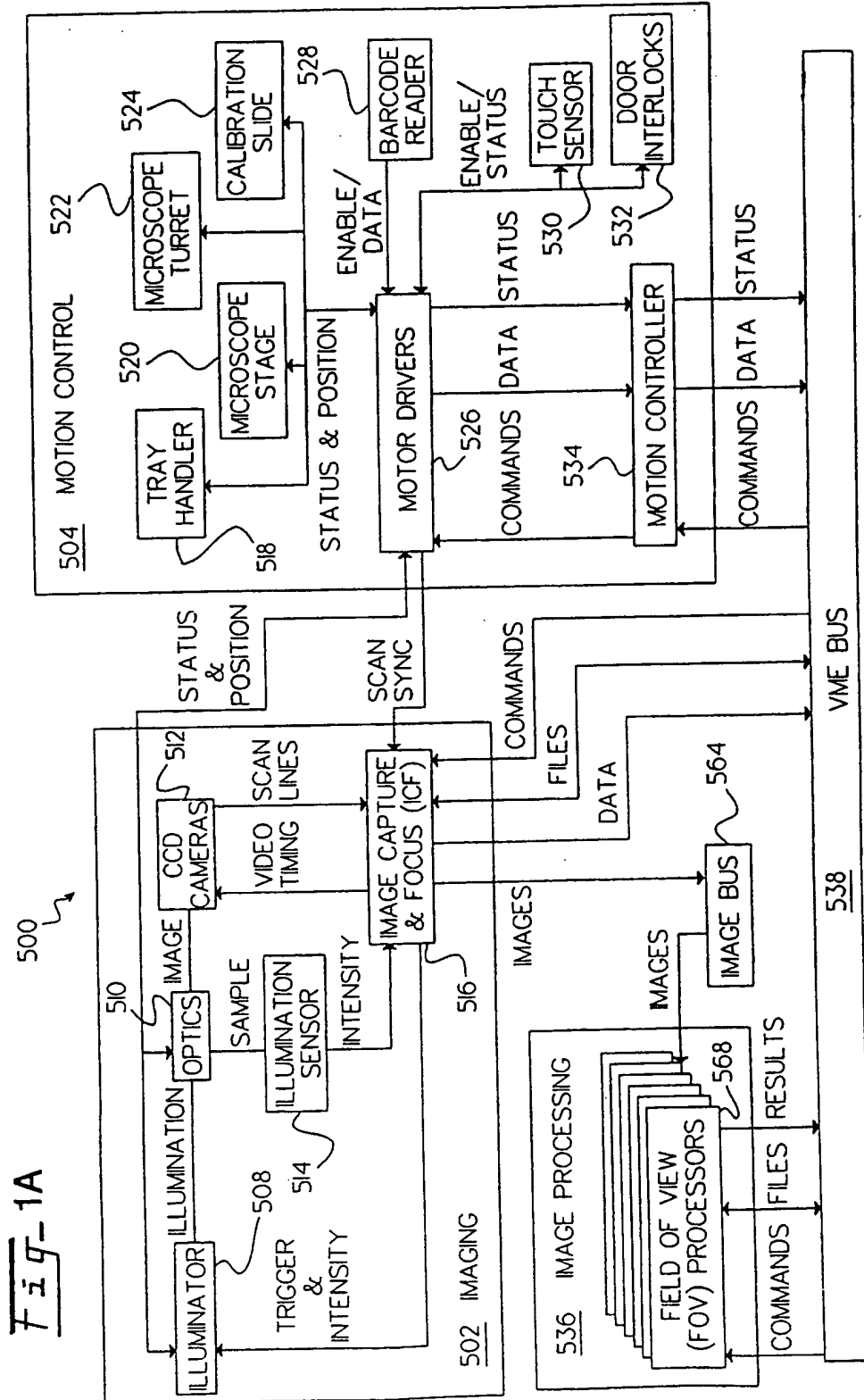
classifier (92) are potentially abnormal, artifact or normal;

(d) a stage 3 classifier (96) for determining whether the potentially abnormal objects from the stage 2 classifier (94) are potentially abnormal or are normal and artifact objects; and

(e) a stage 4 classifier (98) for determining whether the potential abnormal objects from the stage 3 classifier (96) are potentially abnormal or are normal artifacts.

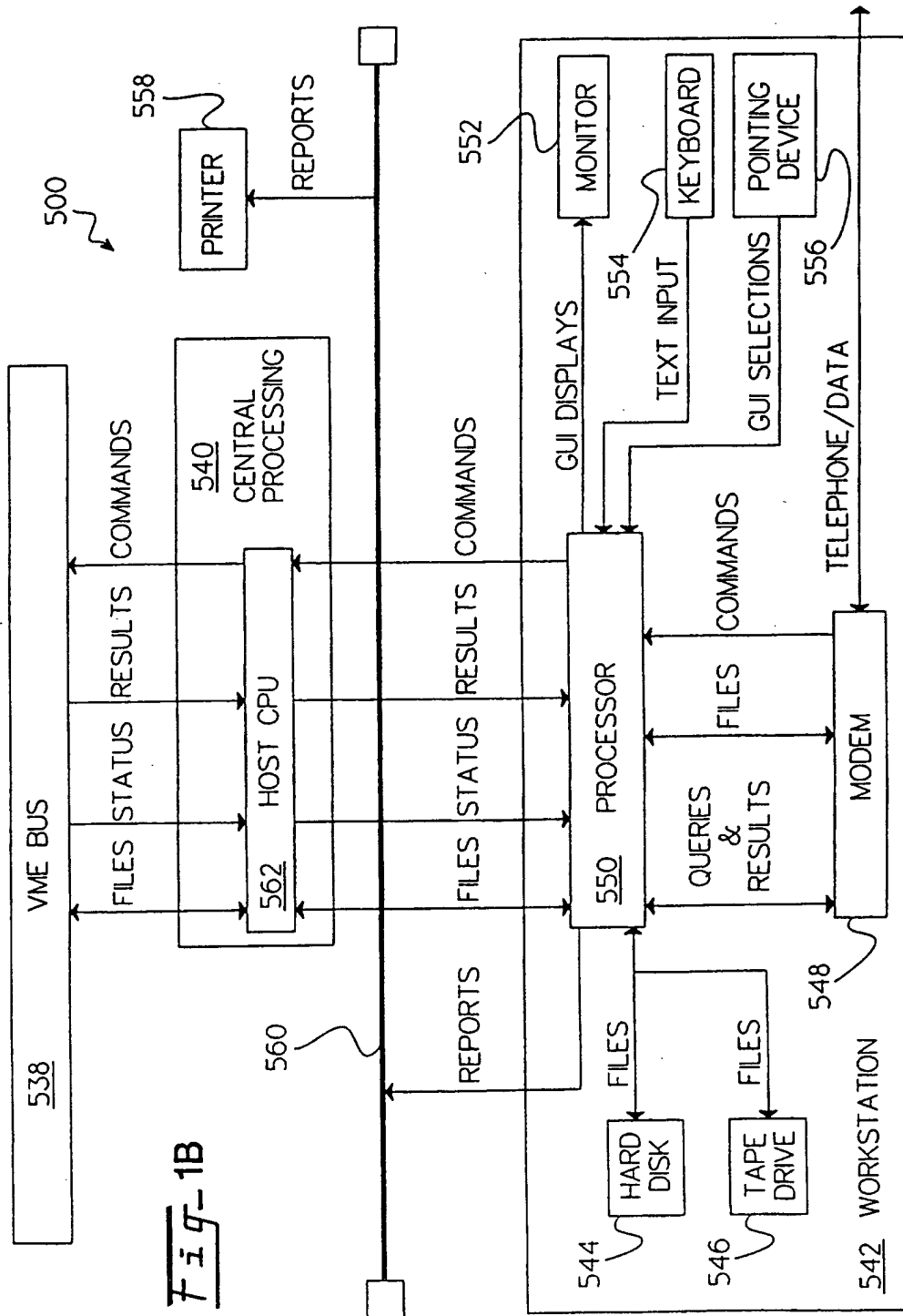
46. The apparatus of claim 27 further comprising a diagnostic classifier means (100) for determining whether the objects of interest (80, 82) in the output of the stage 3 classifier (96) are low grade squamous intraepithelial lesions, potential high grade squamous intraepithelial lesions, cancerous lesions or normal artifacts.

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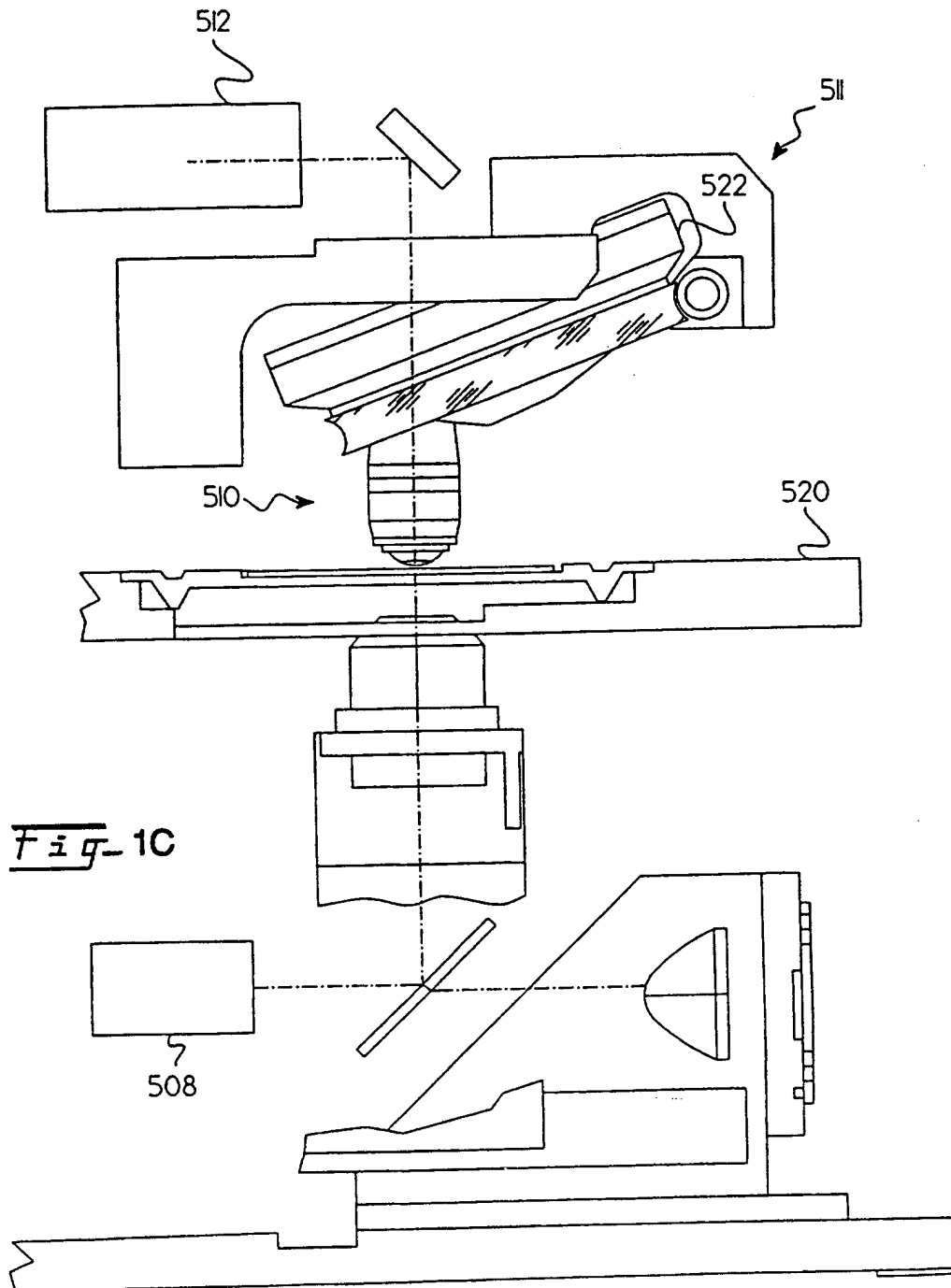




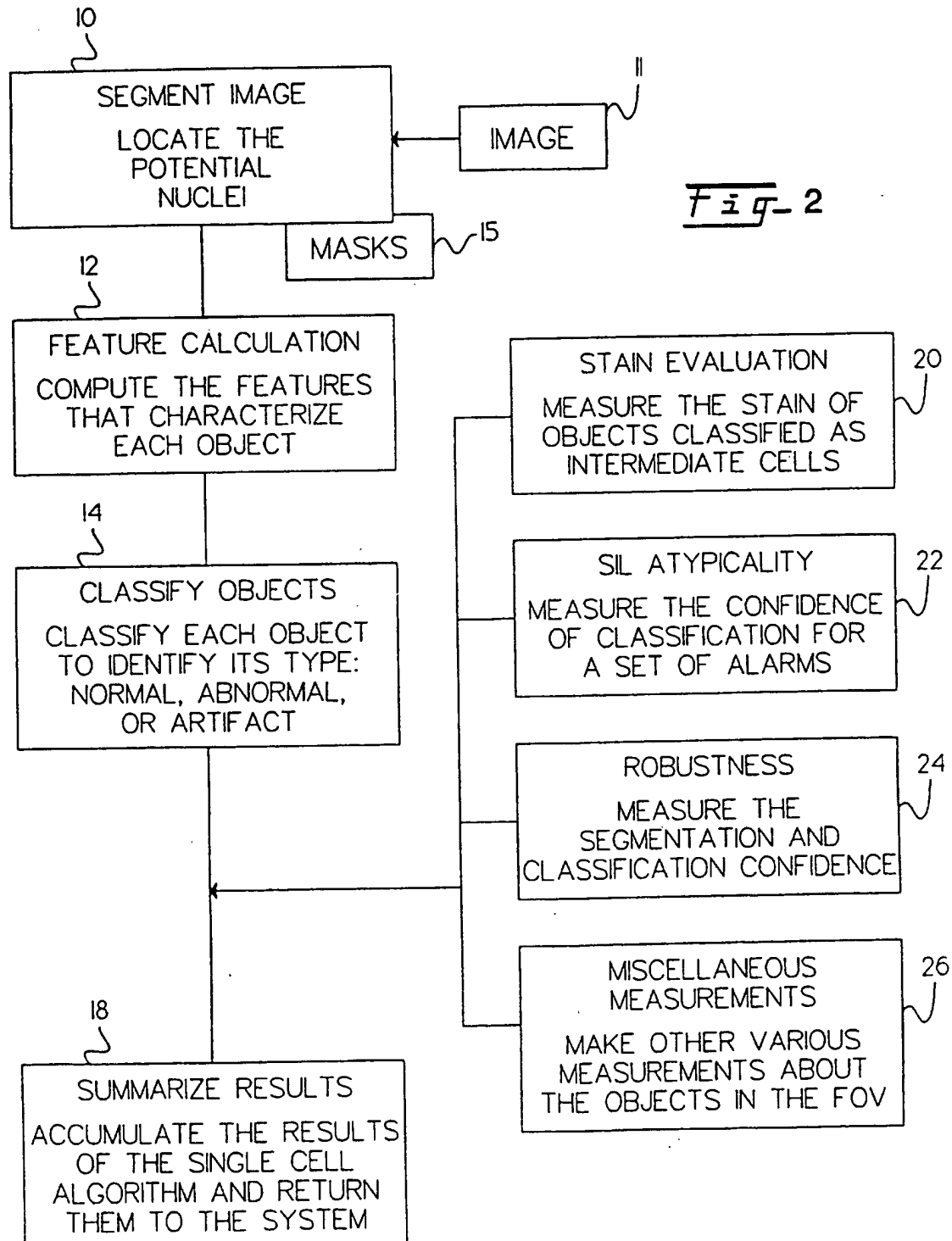
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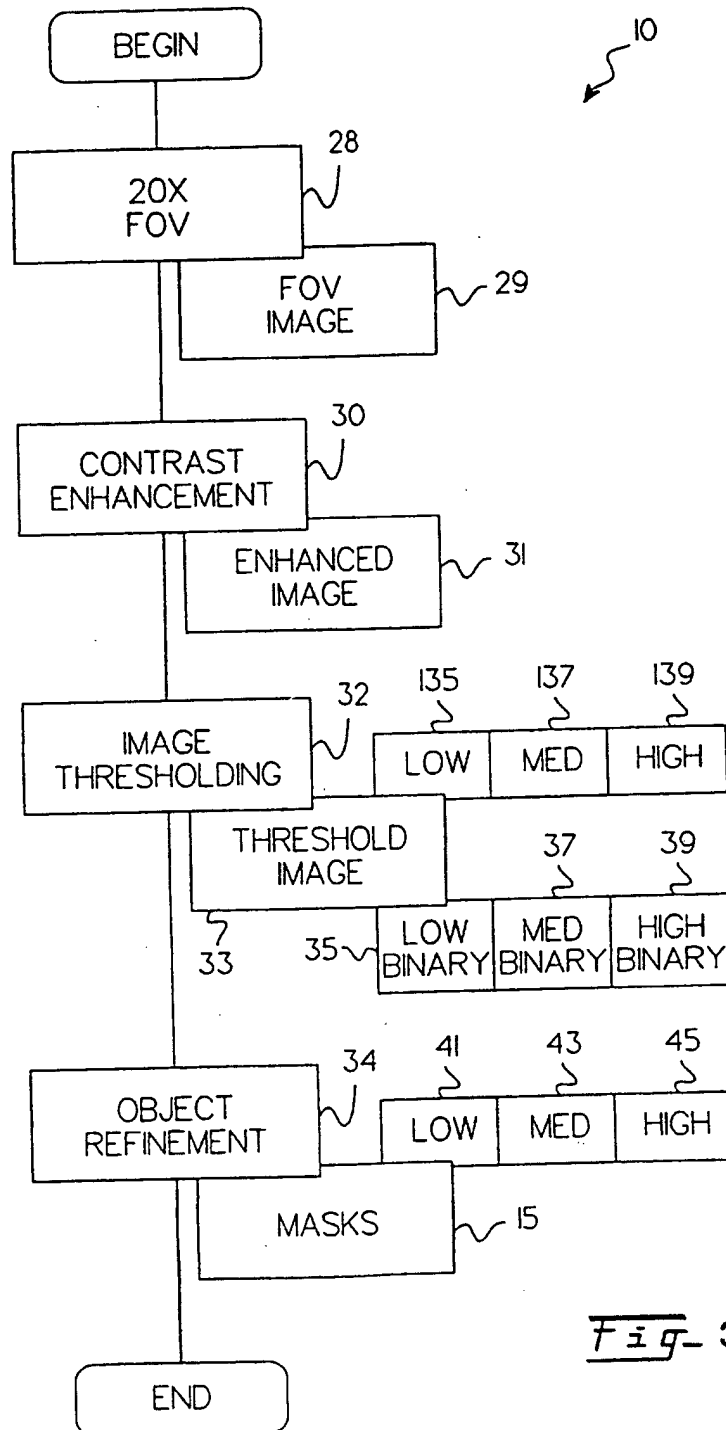
3/19



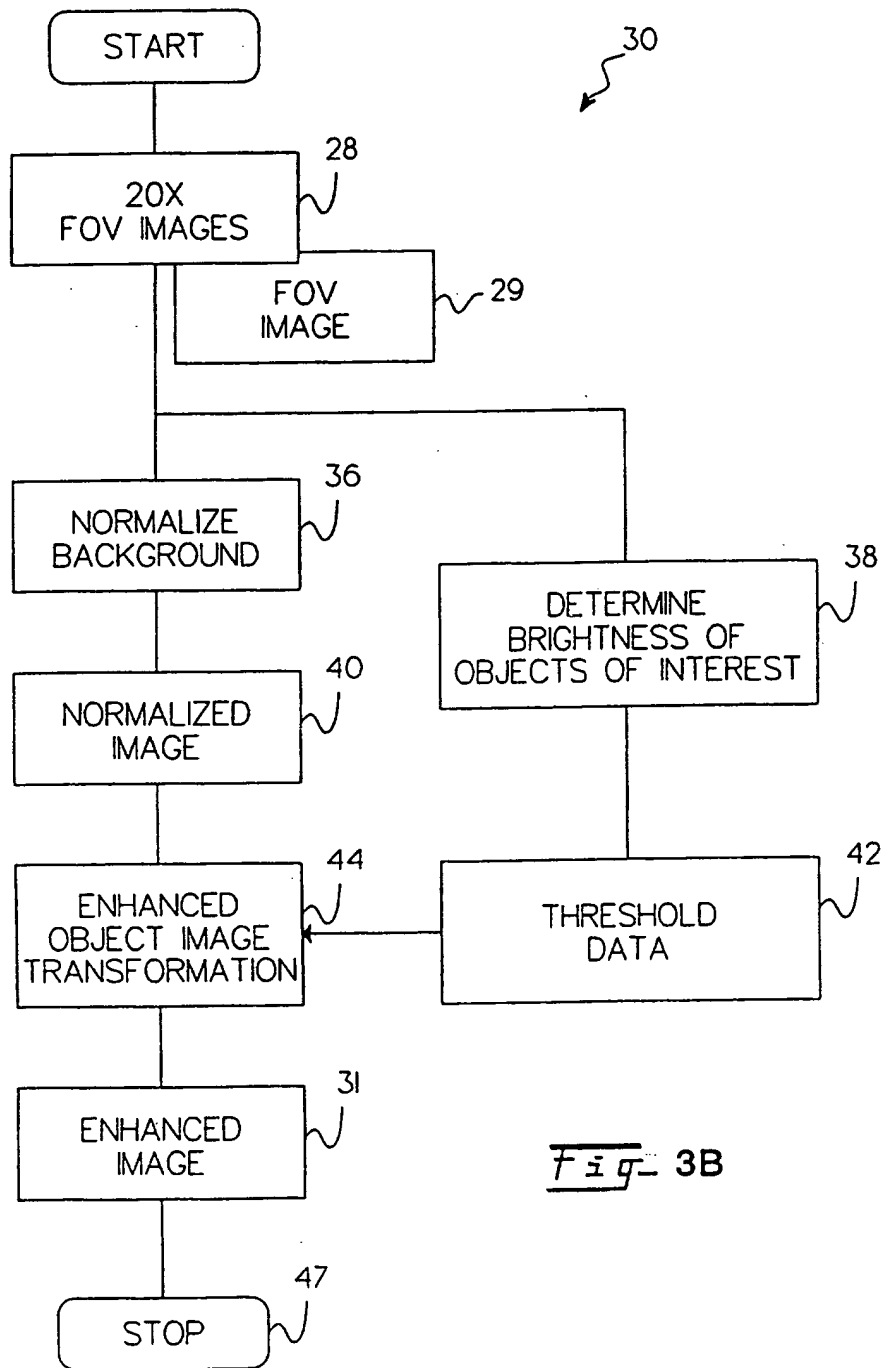
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Fig. 3A

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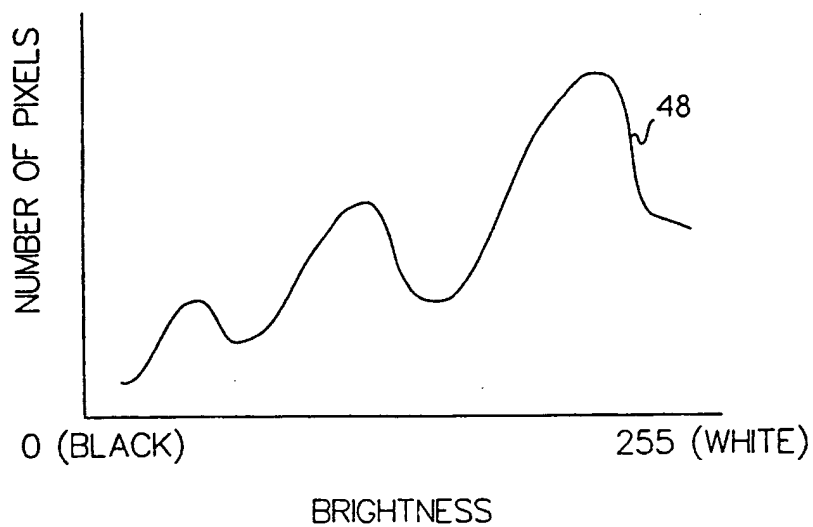


Fig- 3C

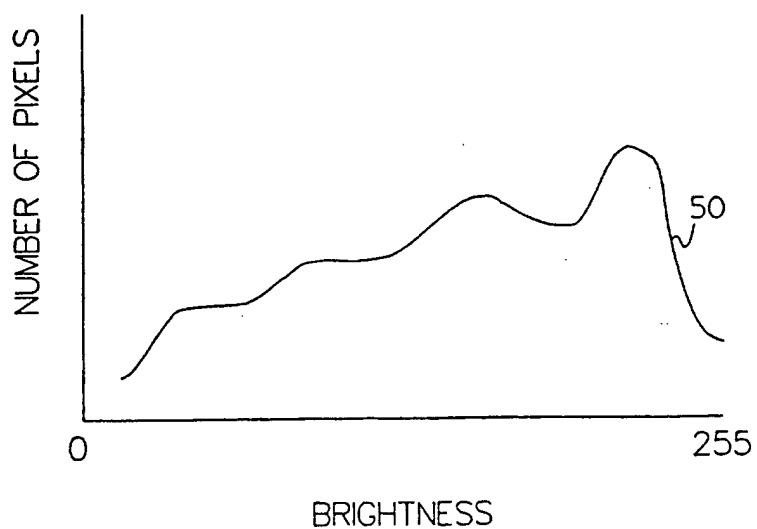
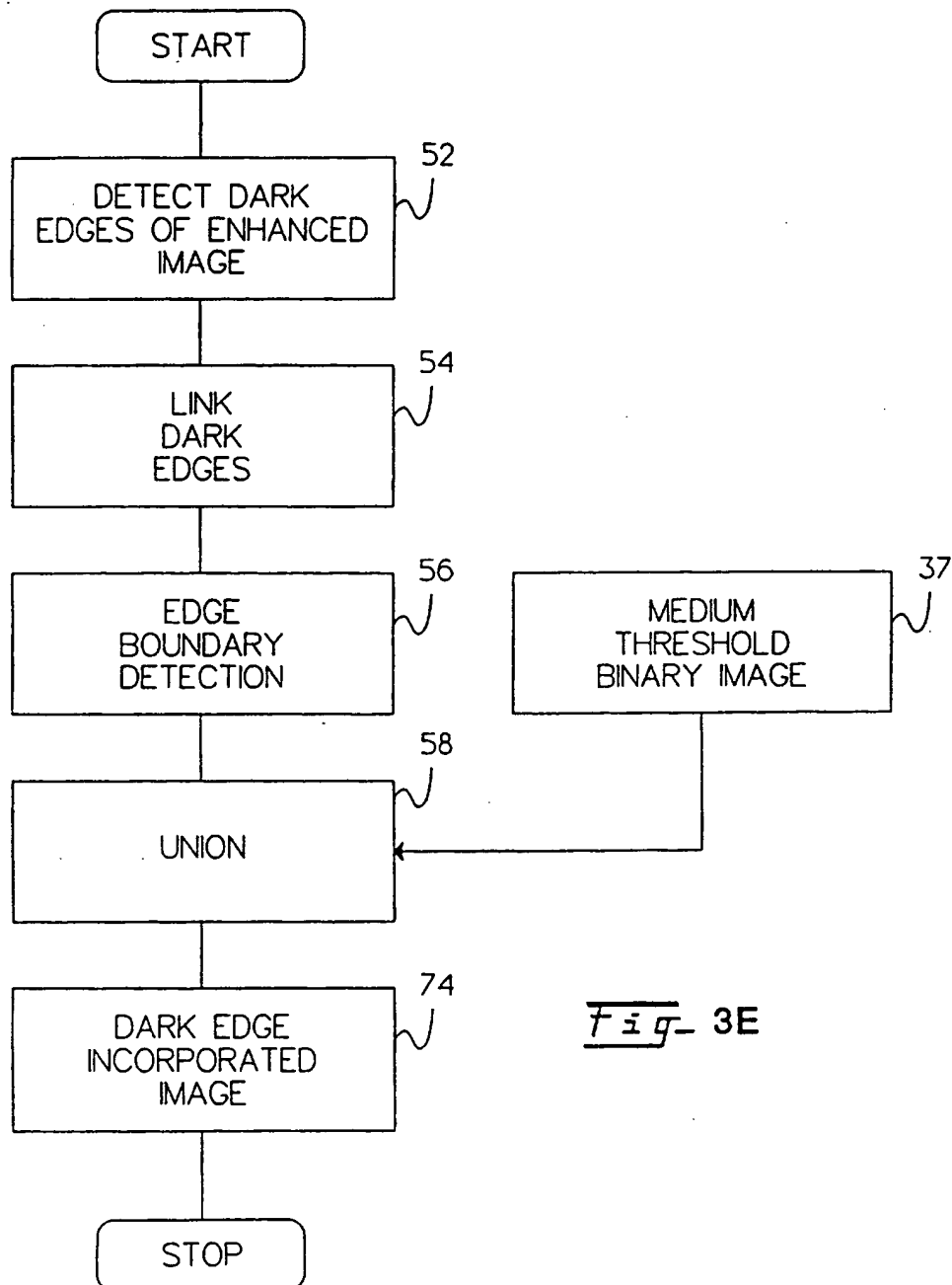
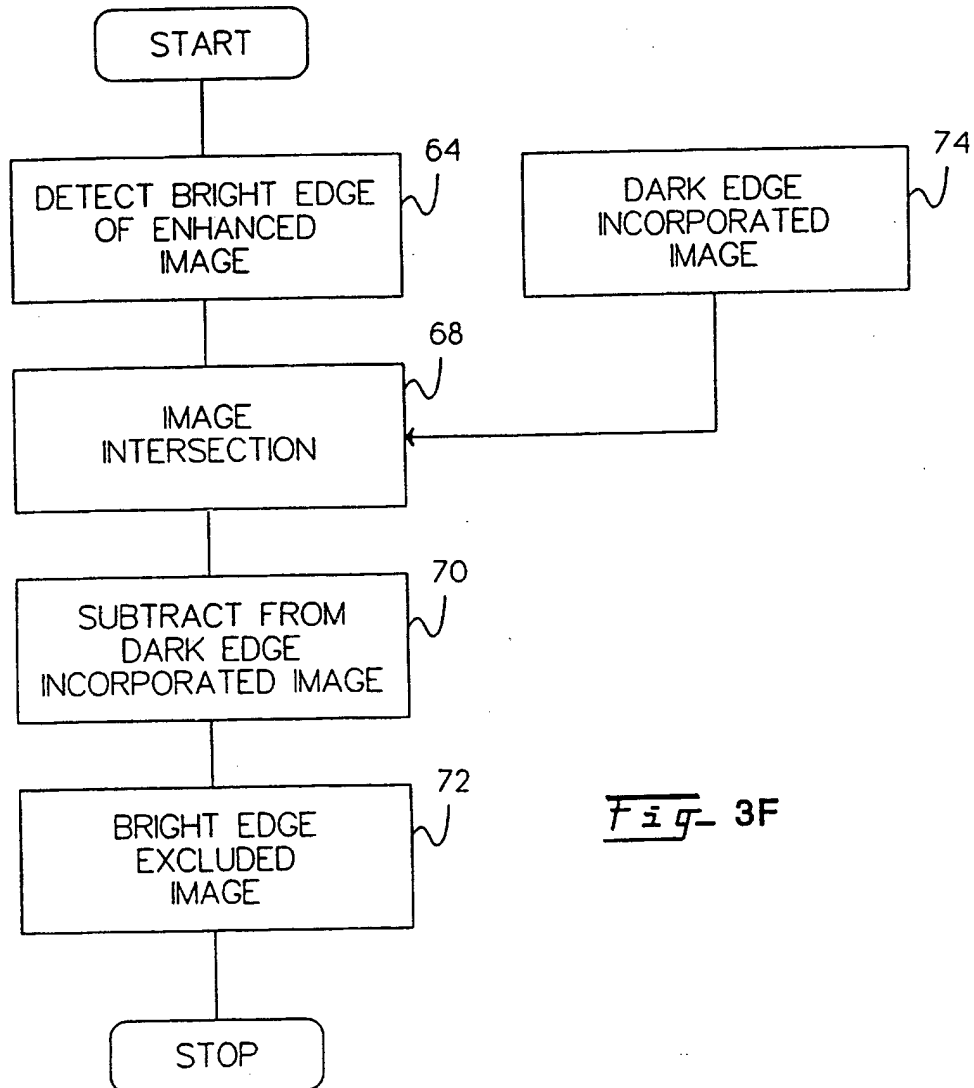


Fig- 3D

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Fig- 3E

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Fig- 3F



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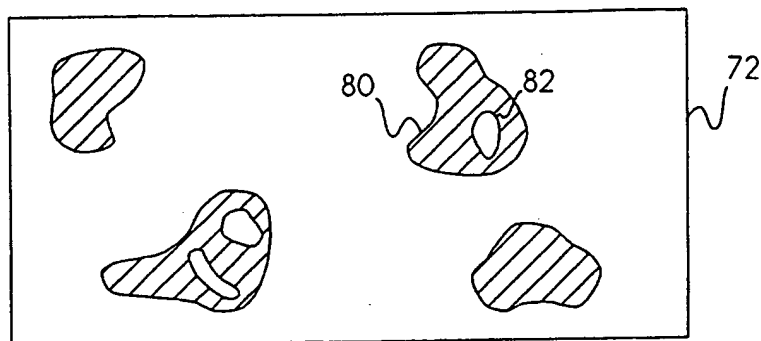


Fig- 3G

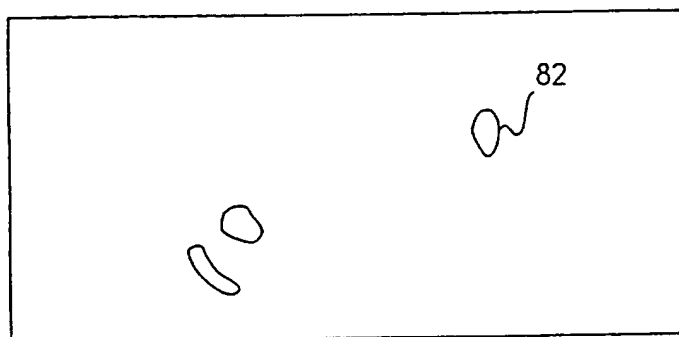


Fig- 3H

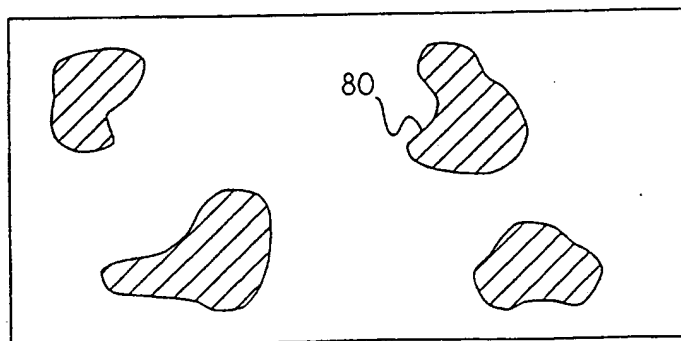


Fig- 3I

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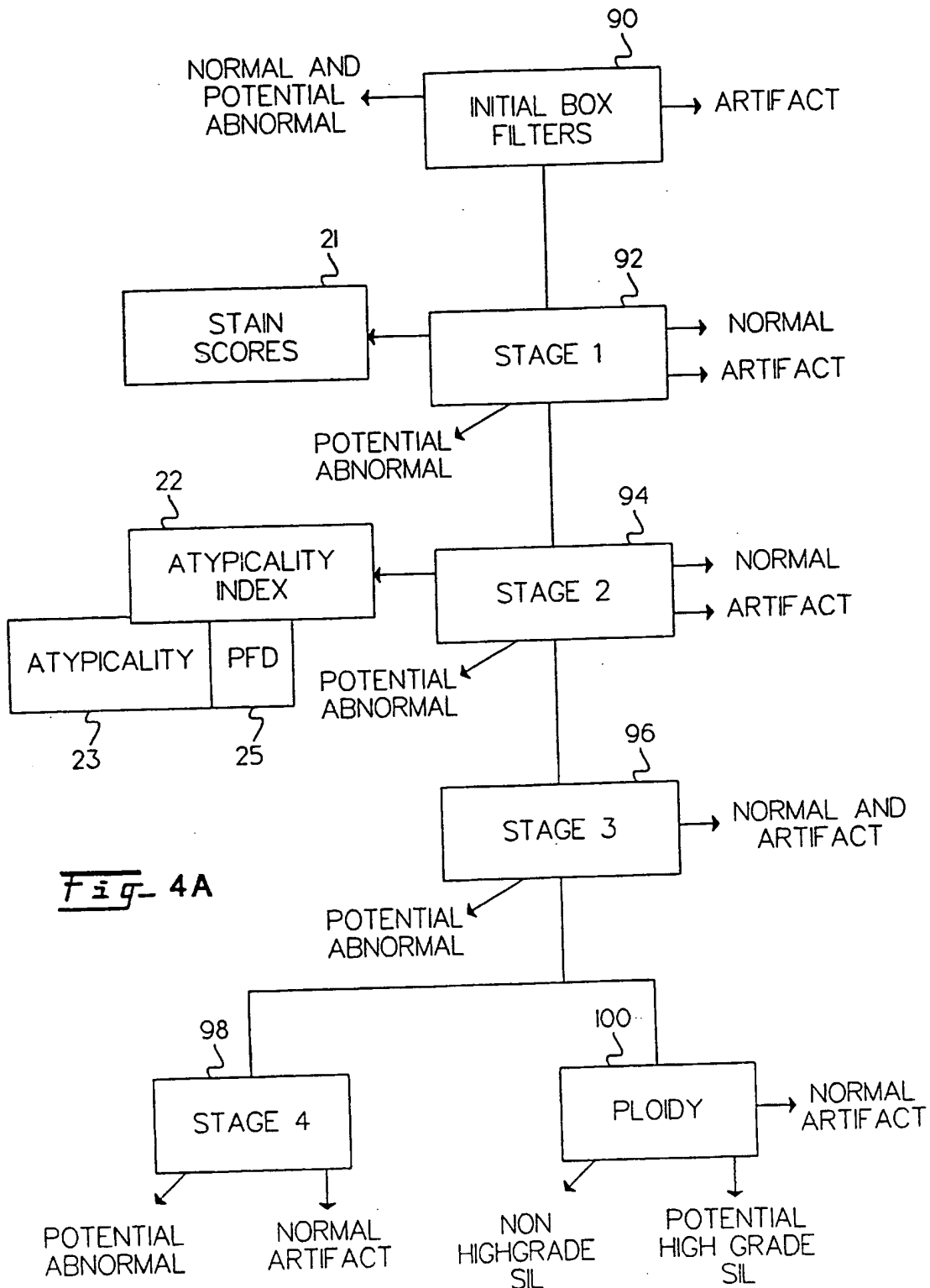
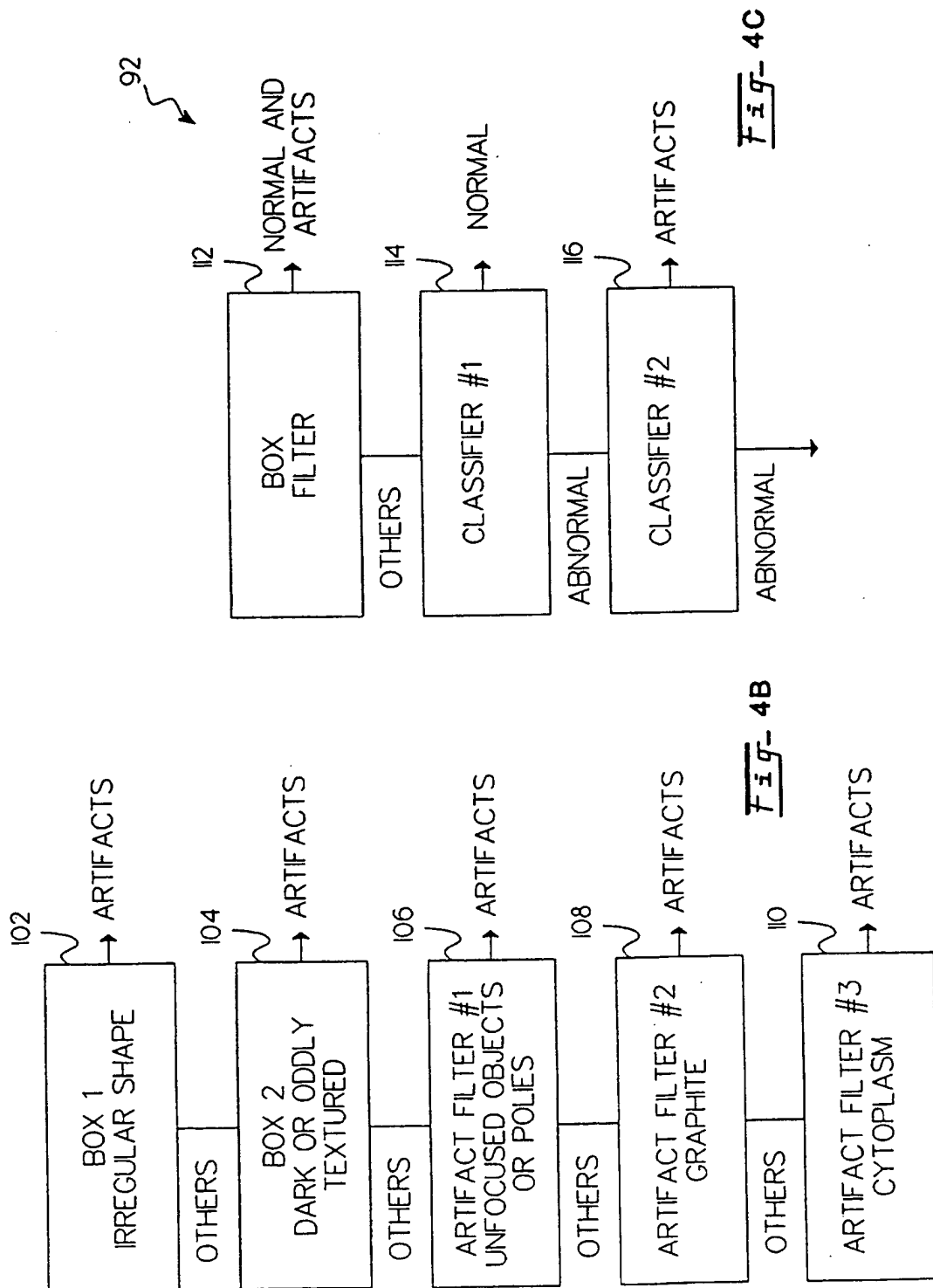
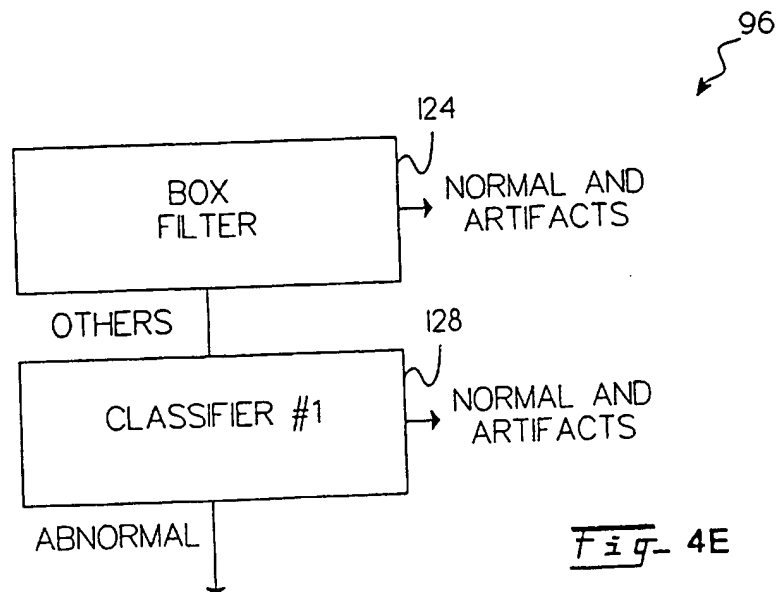
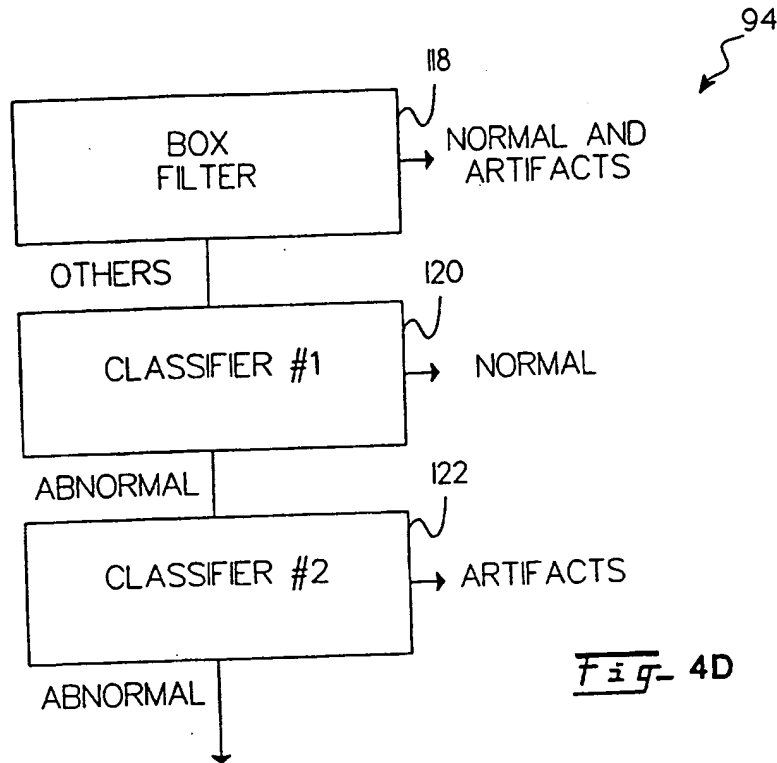


Fig- 4A

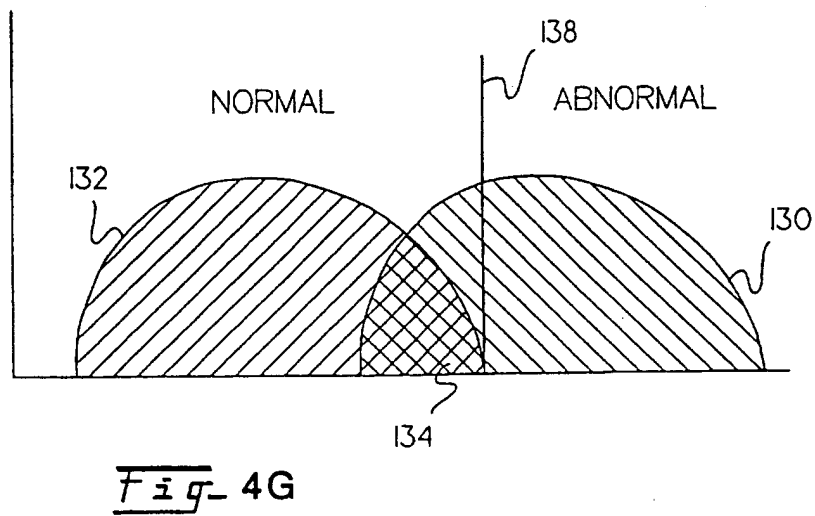
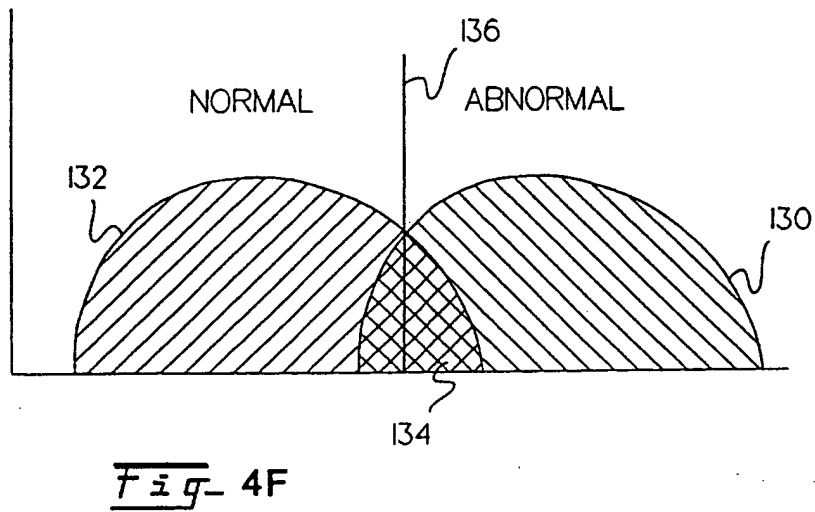
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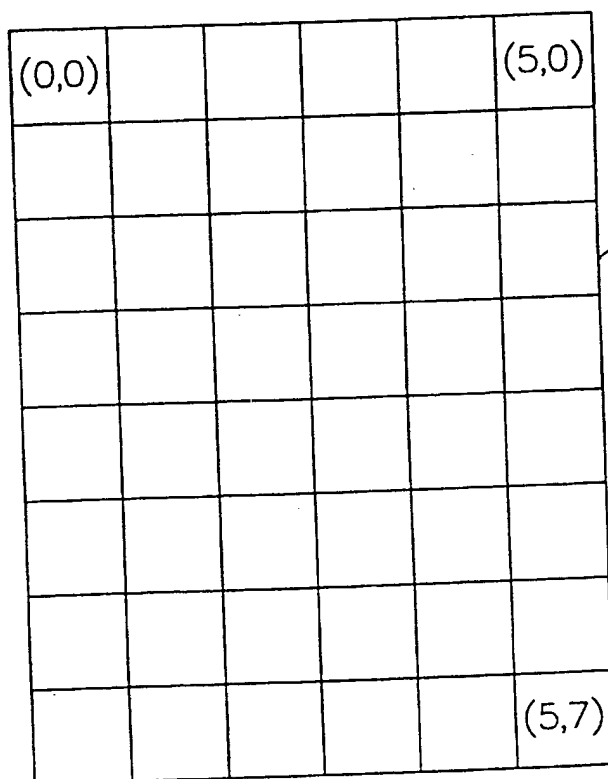
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LARGE  
LIGHT  
OBJECTS

SIZE

10D

140

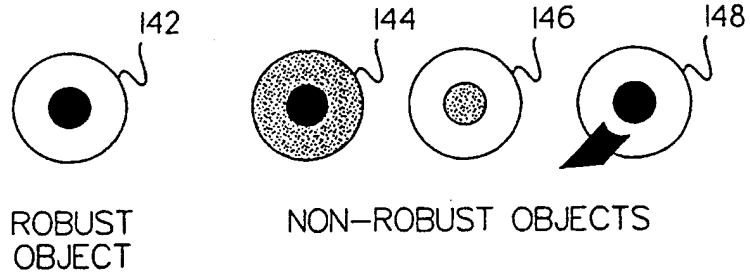


SMALL  
DARK  
OBJECTS

Fig- 5

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Fig- 6A



FEATURE 1

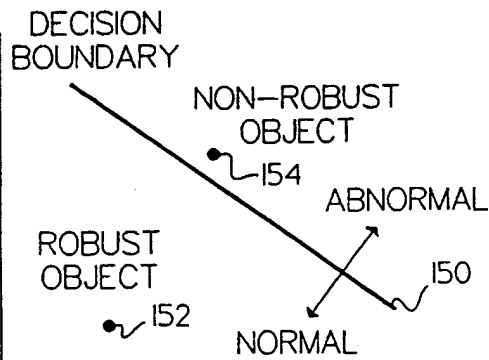
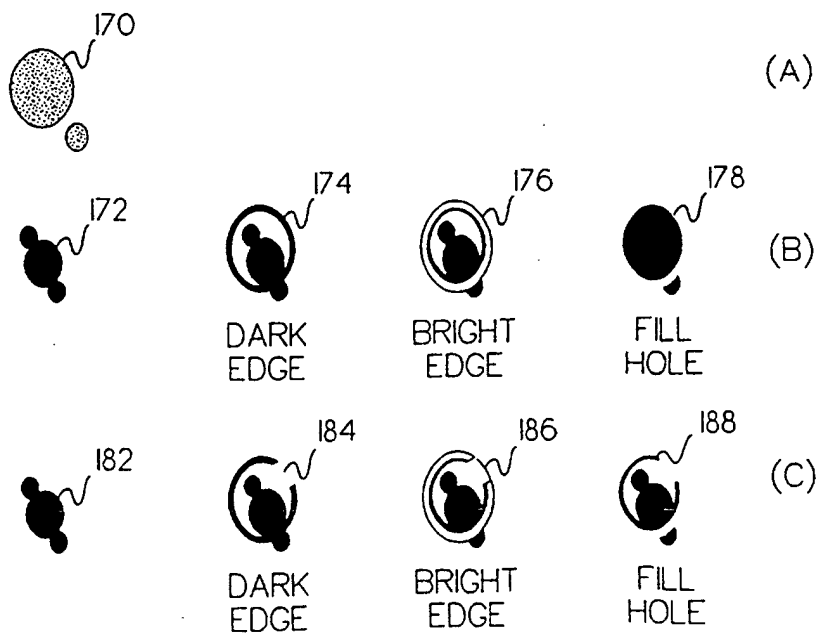


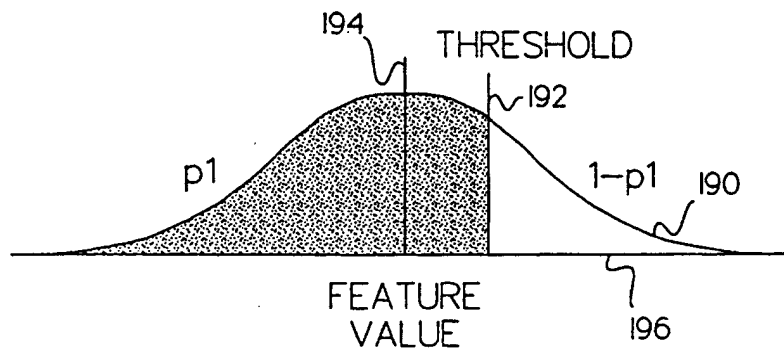
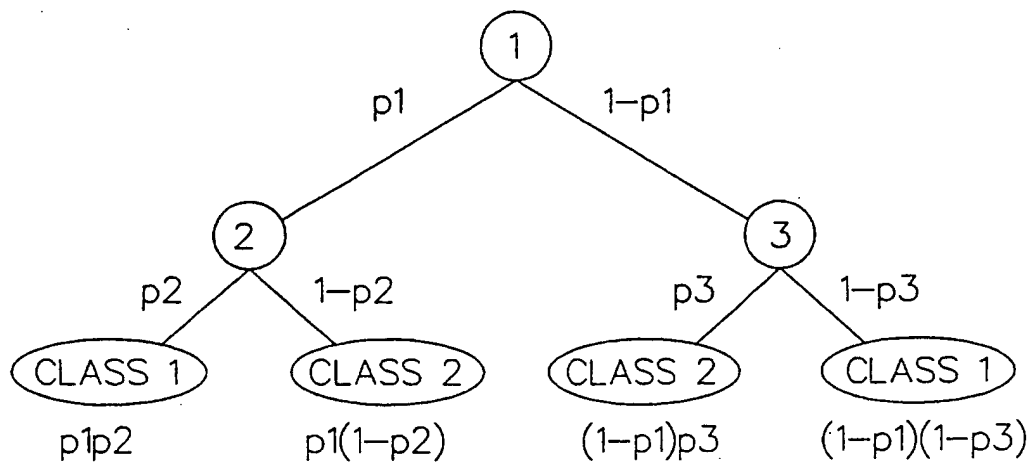
Fig- 6B

FEATURE 2

Fig- 6C

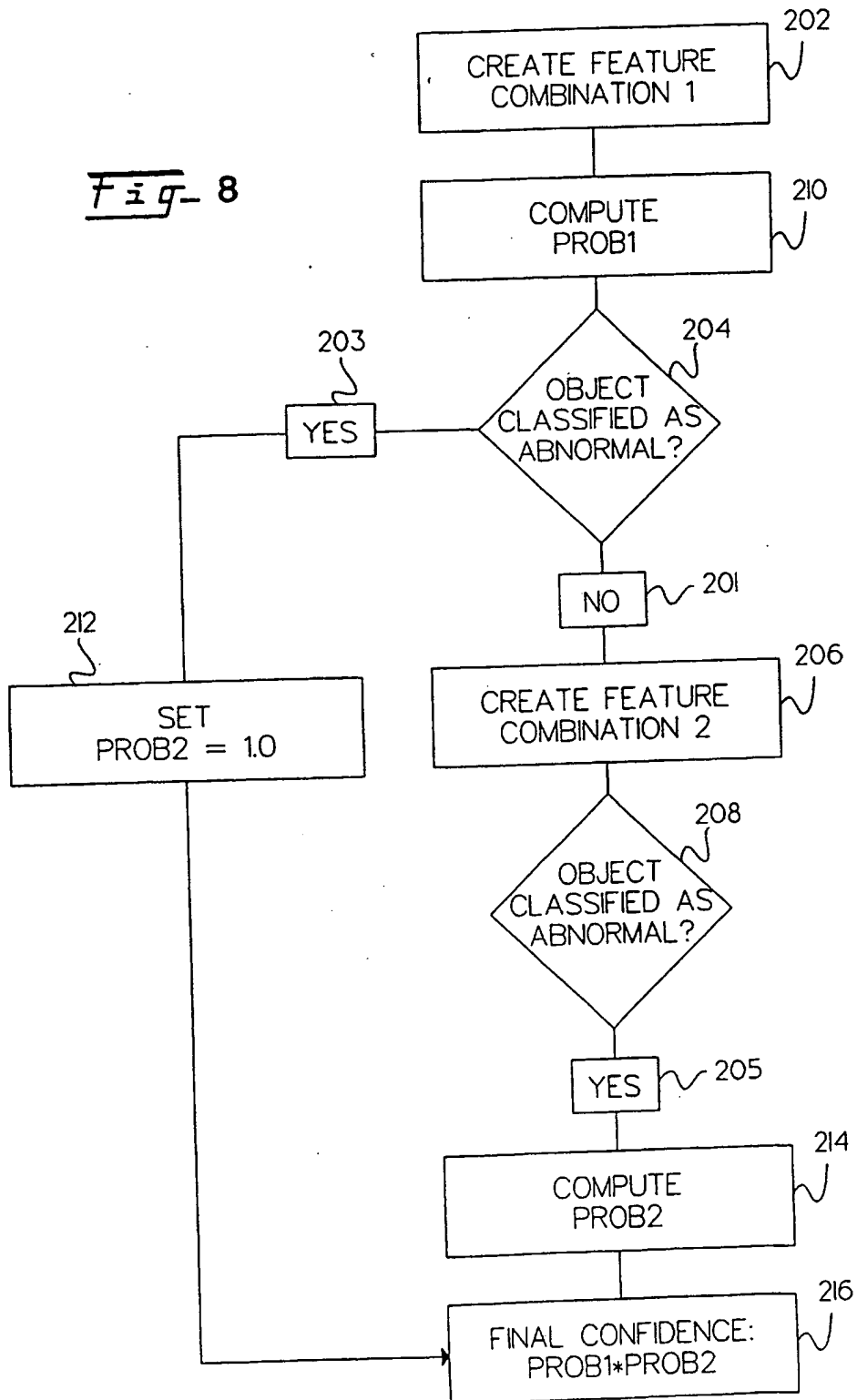


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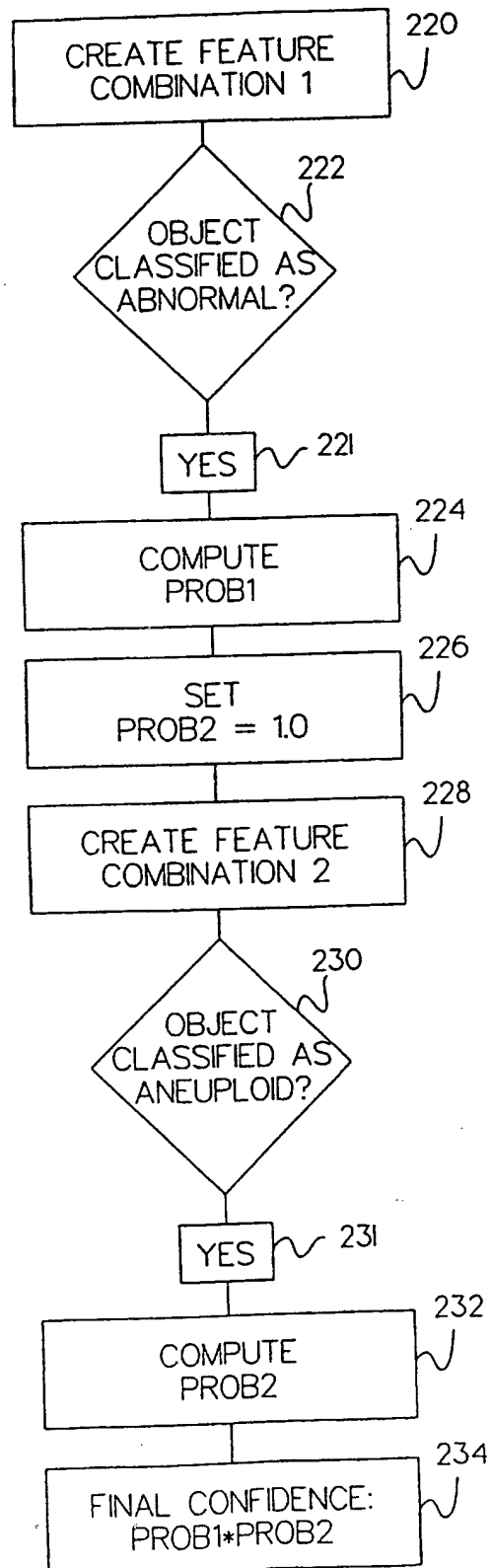
Fig- 7AFig- 7B



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Fig- 8

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Fig- 9

# INTERNATIONAL SEARCH REPORT

International application No.

PCT/US95/11492

## A. CLASSIFICATION OF SUBJECT MATTER

IPC(6) : G06K 9/00, 9/34, 9/46, 9/66, 9/62, 9/38, 9/40

US CL : 382/133, 173, 190, 224, 270, 274, 275

According to International Patent Classification (IPC) or to both national classification and IPC

## FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)

U.S. : 382/133, 134, 128, 171, 172, 173, 190, 199, 204, 224, 254, 270, 274, 275

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)

APS, search terms: cell, specimen, identification, classification, feature, segmentation, enhancement, contrast, thresholding, normal, abnormal, artifact.

## C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
Y	US, A 4,097,845 (BACUS) 27 JUNE 1978, the abstract, Figure 4, col. 7, line 33 - col. 8, line 57, and col. 10, line 19 - col. 11, line 59.	1-18, 42-44
Y	US, A 4,513,438 (GRAHAM ET AL) 23 APRIL 1985, the abstract, Figures 5A, 5B, and col. 5, line 32 - col. 7, line 41.	1-18, 42-44
	US, A, 5,287,272 (RUTENBERG ET AL) 15 FEBRUARY 1994, Figures 4, 3A-3C, and col. 2, line 16 - col. 3, line 65.	1-18, 42-44
A	US, A, 4,199,748 (BACUS) 22 APRIL 1980.	1-46
A	US, A, 5,016,283 (BACUS ET AL) 14 MAY 1991.	1-46

☐ Further documents are listed in the continuation of Box C. ☐ See patent family annex.

* Special categories of cited documents:	*T later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention
*A document defining the general state of the art which is not considered to be part of particular relevance	*X document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone
*E earlier document published on or after the international filing date	*Y document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art
*L document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified)	*G document member of the same patent family
*O document referring to an oral disclosure, use, exhibition or other means	
*P document published prior to the international filing date but later than the priority date claimed	

Date of the actual completion of the international search

FEBRUARY 1996

Date of mailing of the international search report

28 FEB 1996

Name and mailing address of the ISA/US  
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# INTERNATIONAL SEARCH REPORT

International application No.  
PCT/US95/11492

## Box I Observations where certain claims were found unsearchable (Continuation of item 1 of first sheet)

This international report has not been established in respect of certain claims under Article 17(2)(a) for the following reasons:

1. ☐ Claims Nos.:  
because they relate to subject matter not required to be searched by this Authority, namely:
2. ☐ Claims Nos.:  
because they relate to parts of the international application that do not comply with the prescribed requirements to such an extent that no meaningful international search can be carried out, specifically:
3. ☐ Claims Nos.:  
because they are dependent claims and are not drafted in accordance with the second and third sentences of Rule 6.4(a).

## Box II Observations where unity of invention is lacking (Continuation of item 2 of first sheet)

This International Searching Authority found multiple inventions in this international application, as follows:

Please See Extra Sheet.

1. ☒ As all required additional search fees were timely paid by the applicant, this international search report covers all searchable claims.
2. ☐ As all searchable claims could be searched without effort justifying an additional fee, this Authority did not invite payment of any additional fee.
3. ☐ As only some of the required additional search fees were timely paid by the applicant, this international search report covers only those claims for which fees were paid, specifically claims Nos.:
4. ☐ No required additional search fees were timely paid by the applicant. Consequently, this international search report is restricted to the invention first mentioned in the claims; it is covered by claims Nos.:

Remark on Protest

- ☐ The additional search fees were accompanied by the applicant's protest.  
☒ No protest accompanied the payment of additional search fees.

## INTERNATIONAL SEARCH REPORT

International application No.  
PCT/US95/11492

### BOX II. OBSERVATIONS WHERE UNITY OF INVENTION WAS LACKING

This ISA found multiple inventions as follows:

Group I, claims 1-17 and 42-44, drawn to a cell identification apparatus for identifying object types of interest.  
Group II, claim 18, drawn to a free-lying cell segmenter.  
Group III, claims 19-37, 45 and 46, drawn to a feature classifier for performing a plurality of stages of feature extraction and object classification on cells in a biological specimen.  
Group IV, claims 38-41, drawn to an apparatus for computing a stain score from a biological specimen.  
The inventions listed as Groups I to IV do not related to a single inventive concept under PCT Rule 13.1 because, under PCT Rule 13.2, they lack the same or corresponding special technical features mentioned above.